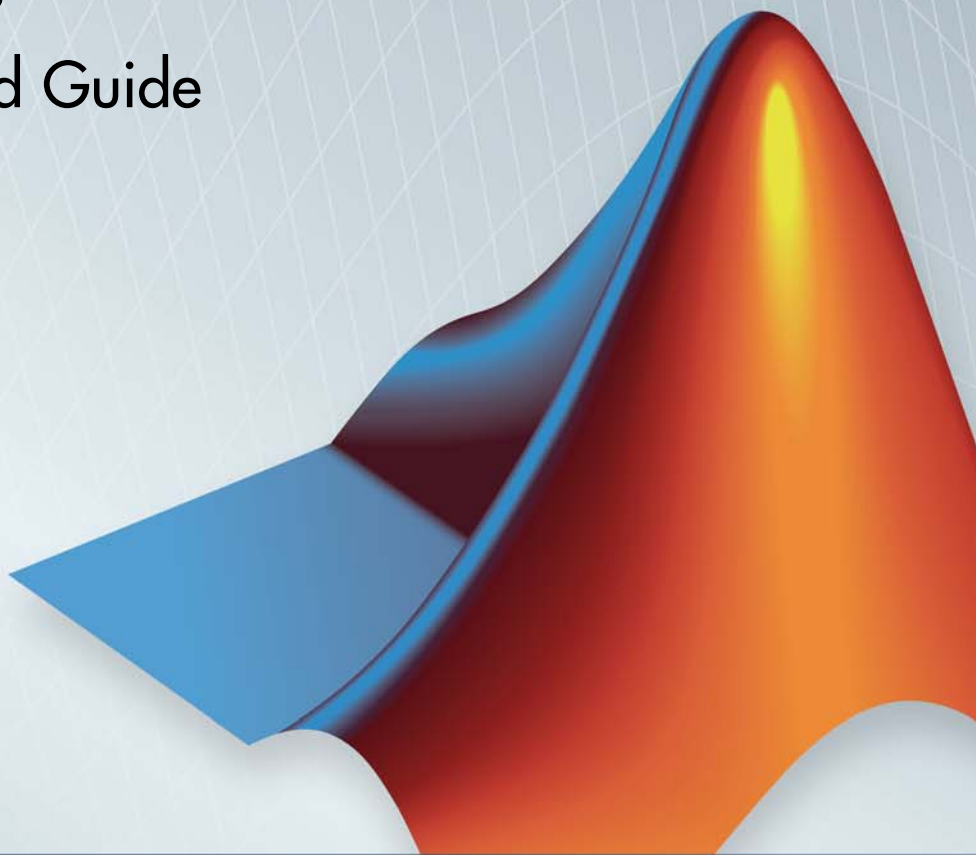


SimMechanics™

Getting Started Guide

R2013b



MATLAB® & SIMULINK®



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SimMechanics™ Getting Started Guide

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Introduction to SimMechanics Software

1

SimMechanics Product Description	1-2
Key Features	1-2
Required and Related Products	1-3
SimMechanics Visualization Requirements	1-3
Support for Recorded Animations	1-3
Related Products	1-3
Representing Machines with SimMechanics Blocks ...	1-5
Open the Library	1-5
Explore the Library	1-5
Start New Multibody Model	1-7
Multibody Model Anatomy	1-8
Basic Model Components	1-8
Applying Forces and Torques	1-11
Sensing Motion	1-13
Multibody Modeling Workflow	1-16
Model Rigid Bodies	1-16
Assemble Multibody Model	1-21
Add Forces, Torques, and Motion Sensors	1-24
Simulate and Analyze model	1-28
Model Simple Link	1-32
Model Overview	1-32
Build Model	1-33
Generate Subsystem	1-34
Visualize Model	1-35
Save Model	1-36
Model Simple Pendulum	1-36

Model Pendulum	1-37
Model Overview	1-37
Build Model	1-38
Specify Gravity	1-39
Add Motion Sensing	1-40
Guide Model Assembly	1-41
Assemble and Simulate Model	1-41
Save Model	1-43
Modeling with SimMechanics First and Second Generations	1-44

Introduction to SimMechanics Software

- “SimMechanics Product Description” on page 1-2
- “Required and Related Products” on page 1-3
- “Representing Machines with SimMechanics Blocks” on page 1-5
- “Start New Multibody Model” on page 1-7
- “Multibody Model Anatomy” on page 1-8
- “Multibody Modeling Workflow” on page 1-16
- “Model Simple Link” on page 1-32
- “Model Pendulum” on page 1-37
- “Modeling with SimMechanics First and Second Generations” on page 1-44

SimMechanics Product Description

Model and simulate multibody mechanical systems

SimMechanics™ provides a multibody simulation environment for 3D mechanical systems, such as robots, vehicle suspensions, construction equipment, and aircraft landing gear. You model the multibody system using blocks representing bodies, joints, constraints, and force elements, and then SimMechanics formulates and solves the equations of motion for the complete mechanical system. Models from CAD systems, including mass, inertia, joint, constraint, and 3D geometry, can be imported into SimMechanics. An automatically generated 3D animation lets you visualize the system dynamics.

You can parameterize your models using MATLAB® variables and expressions, and design control systems for your multibody system in Simulink®. You can add electrical, hydraulic, pneumatic, and other components to your mechanical model using Simscape™ and test them all in a single simulation environment. To deploy your models to other simulation environments, including hardware-in-the-loop (HIL) systems, SimMechanics supports C-code generation (with Simulink Coder™).

Key Features

- Blocks and modeling constructs for simulating and analyzing 3D mechanical systems in Simulink
- Rigid body definition using standard geometry and custom extrusions defined in MATLAB
- Automatic calculation of mass and inertia tensor
- Simulation modes for analyzing motion and calculating forces
- Visualization and animation of multibody system dynamics with 3D geometry
- SimMechanics Link utility, providing an interface to Pro/ENGINEER®, SolidWorks®, and Autodesk Inventor, and an API for interfacing with other CAD platforms
- Support for C-code generation (with Simulink Coder)

Required and Related Products

In this section...
“SimMechanics Visualization Requirements” on page 1-3
“Support for Recorded Animations” on page 1-3
“Related Products” on page 1-3

SimMechanics Visualization Requirements

SimMechanics visualization requires Silicon Graphics OpenGL® graphics support on your system to display and animate SimMechanics models.

You can improve your speed and graphics resolution by adding a graphics accelerator hardware card to your system. Animation of simulations is sensitive to central processor and graphics card speed and memory. Experiment with graphics hardware and system settings to find a reasonable compromise between quality and speed for your system.

Support for Recorded Animations

You can record simulation animations in Microsoft Audio Video Interleave® (AVI) format using SimMechanics visualization. Animations are recorded as compressed AVI files with the default Motion JPEG codec. This codec is available on most operating systems.

To play back AVI files, you need an AVI-compatible media application. MATLAB has an internal movie player compatible with AVI. You can also use an external AVI-compatible player.

Note SimMechanics visualization does not support uncompressed AVI recording.

Related Products

You can extend the capability of SimMechanics using other physical modeling products found in the Simscape family. Each physical modeling product gives

you a set of block libraries with which you can model common components found in industry and academia: rigid bodies, gears, valves, solenoids, etc.

With the physical modeling products, you can model not only mechanical systems, but also electrical, hydraulic, and power systems. You can model each system separately, and then integrate the systems into a single multiphysics model where you can analyze combined system performance.

Physical Modeling Product Family

The physical modeling family includes five products:

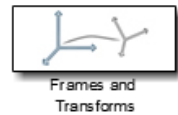
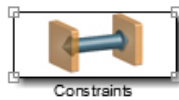
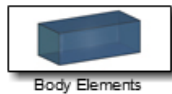
- SimDriveline™, for modeling and simulating drivetrain systems
- SimElectronics®, for modeling and simulating electronic systems
- SimHydraulics®, for modeling and simulating hydraulic systems
- SimMechanics, for modeling and simulating three-dimensional mechanical systems
- SimPowerSystems™, for modeling and simulating electrical power systems

Representing Machines with SimMechanics Blocks

To model a 3-D multibody system, you use the SimMechanics block library. This library contains seven sublibraries that you represent the different model components with. Components that you can represent include rigid bodies, joints, gear and general kinematic constraints, forces and torques, and motion sensors.

Open the Library

To open the SimMechanics block library, at the MATLAB command line enter `sm_lib`. The SimMechanics block library opens in a new window. The figure shows the library that opens.



SimMechanics™ Product Library

Explore the Library

The table provides an overview of the SimMechanics sublibraries. Open each sublibrary to explore its blocks. For detailed information about a block, see its reference page. You can do this by double-clicking the block, then clicking **Help** in the block dialog box.

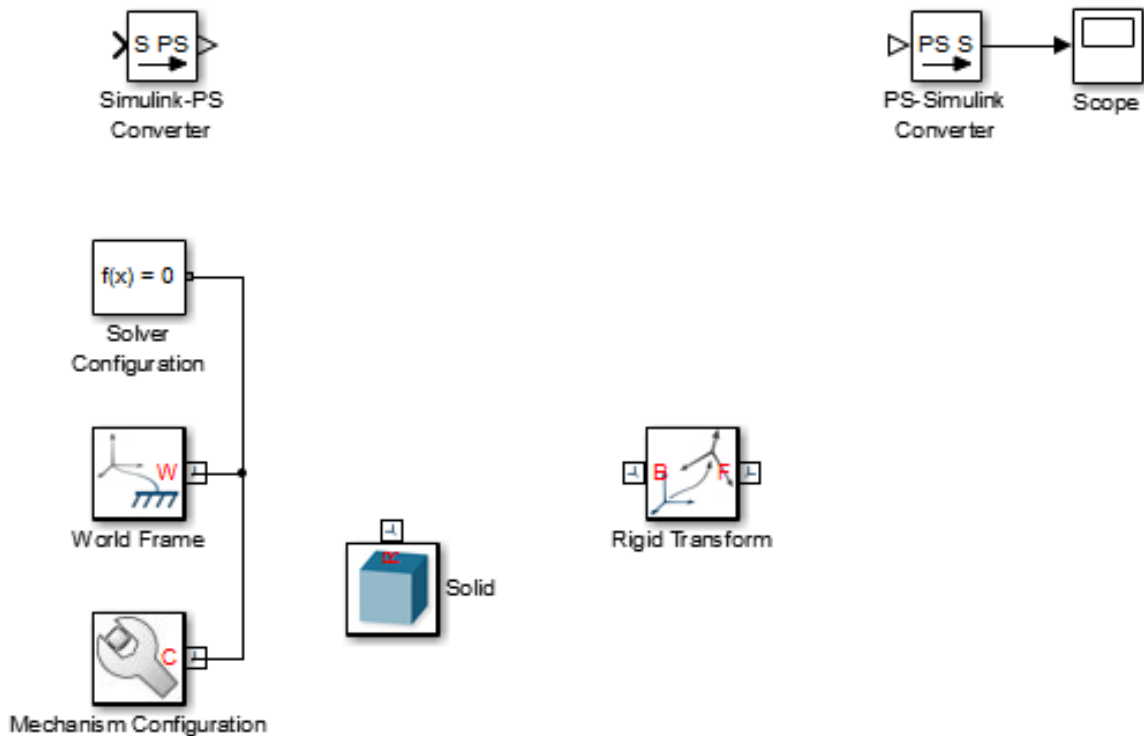
Sublibrary	Description
Body Elements	Represent the solid properties of a rigid body
Constraints	Constrain the relative motion between two rigid body frames
Forces and Torques	Apply internal and external forces and torques on or between rigid body frames
Gears, Couplings and Drives	Couple the motion of two rigid body frames
Joints	Represent the mechanical degrees of freedom between two rigid body frames
Utilities	Represent the external environment of a multibody system

Related Examples

- “Start New Multibody Model” on page 1-7

Start New Multibody Model

You can start a new multibody model from the MATLAB command line. To do this, enter `smnew`. A new model window opens with commonly used blocks. The SimMechanics block library also opens. The figure shows the new model window that you see. Drag blocks from the library into the model window to begin modeling a new multibody system.



Concepts

- “Representing Machines with SimMechanics Blocks” on page 1-5

Multibody Model Anatomy

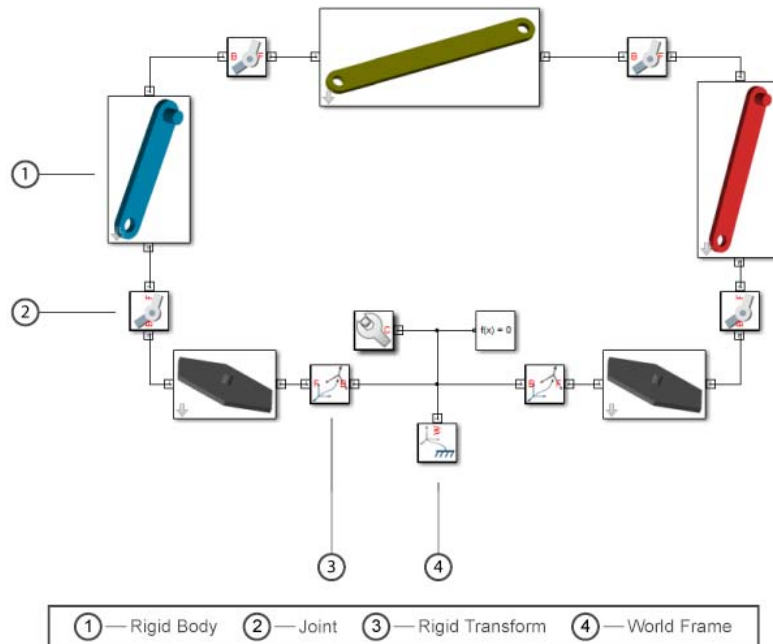
In this section...
“Basic Model Components” on page 1-8
“Applying Forces and Torques” on page 1-11
“Sensing Motion” on page 1-13

With SimMechanics, you represent a multibody system using blocks. Like all physical modeling products, each block represents a physical component or an abstract entity fundamental to physical modeling, e.g. frames and frame transforms.

By connecting the blocks with connection lines, you define the relationships that unite the physical components into a single system (or subsystem). In a basic model, these physical components include rigid bodies and joints. You can also add forces and torques, motion sensors, and kinematic constraints such as gears.

Basic Model Components

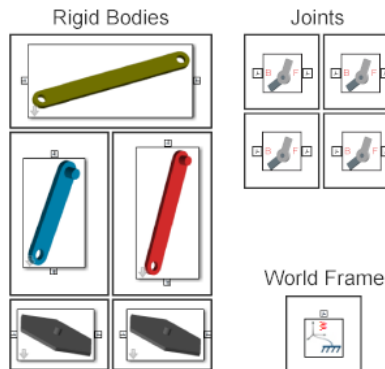
The figure shows the block diagram of a multibody system—the four-bar linkage. This model contains subsystem blocks to represent the links and pivot mounts. These represent the rigid bodies of the model. The model contains also four Revolute Joint blocks. These represent the joints in the model. Combined, these blocks form the foundation of this model.



While important, rigid body subsystem and joint blocks are not sufficient to represent the four-bar linkage. Other blocks serve important purposes. These include World Frame, Rigid Transform, Mechanism Configuration, and Solver Configuration blocks. The table summarizes their purpose in a multibody model.

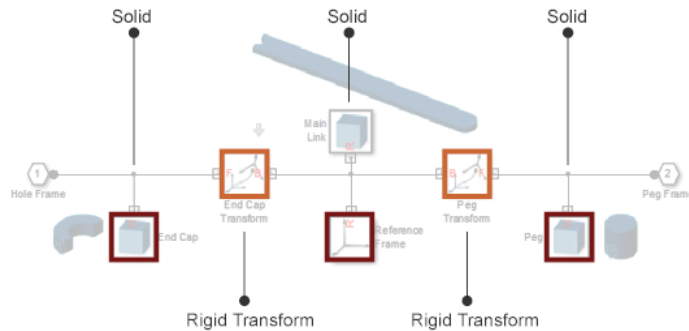
Block	Purpose
World Frame	Provides the ultimate reference frame in a model. All remaining frames are defined with respect to this frame. It is inertial and it defines absolute rest.
Rigid Transform	Applies a fixed spatial relationship between frames. This block defines the offset distance and angle between two frames.
Mechanism Configuration	Identifies the gravity vector in a model.
Solver Configuration	Provides essential simulation parameters required to simulate the model.

The figure breaks the four-bar model into its logical components. These are the physical components and abstract entities that you need in order to represent this system.



Each rigid body subsystem contains SimMechanics blocks that represent solids and their spatial relationships. The blocks are Solid and Rigid Transform. The figure shows the blocks that model one of the binary links. Three Solid blocks represent the three solid sections of this rigid body—main, peg, and hole sections. Two Rigid Transform blocks represent the fixed spatial

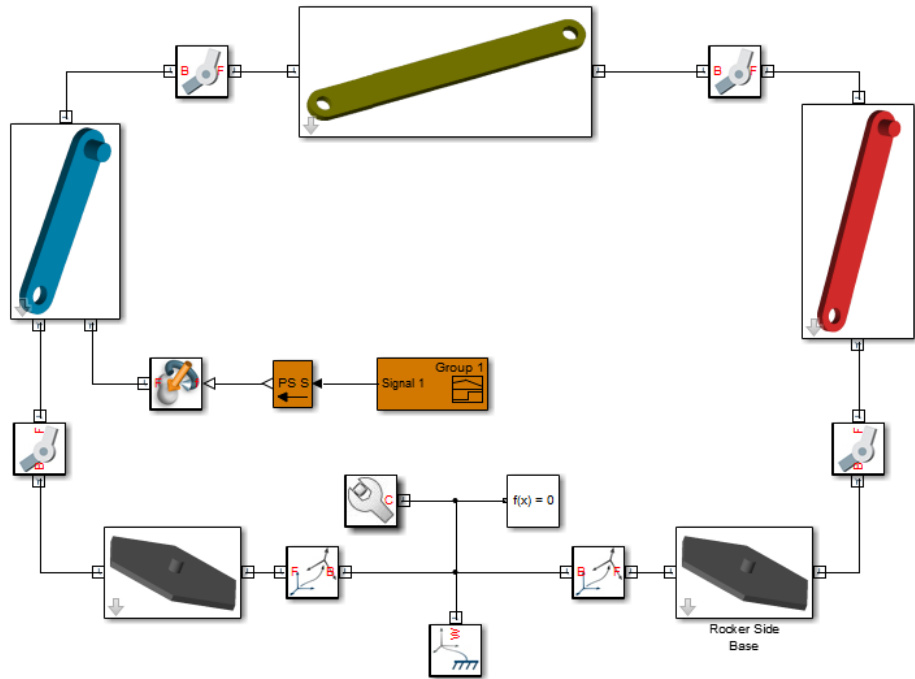
relationships between the three solids. You use them to position the peg and hole sections at the ends of the main section.



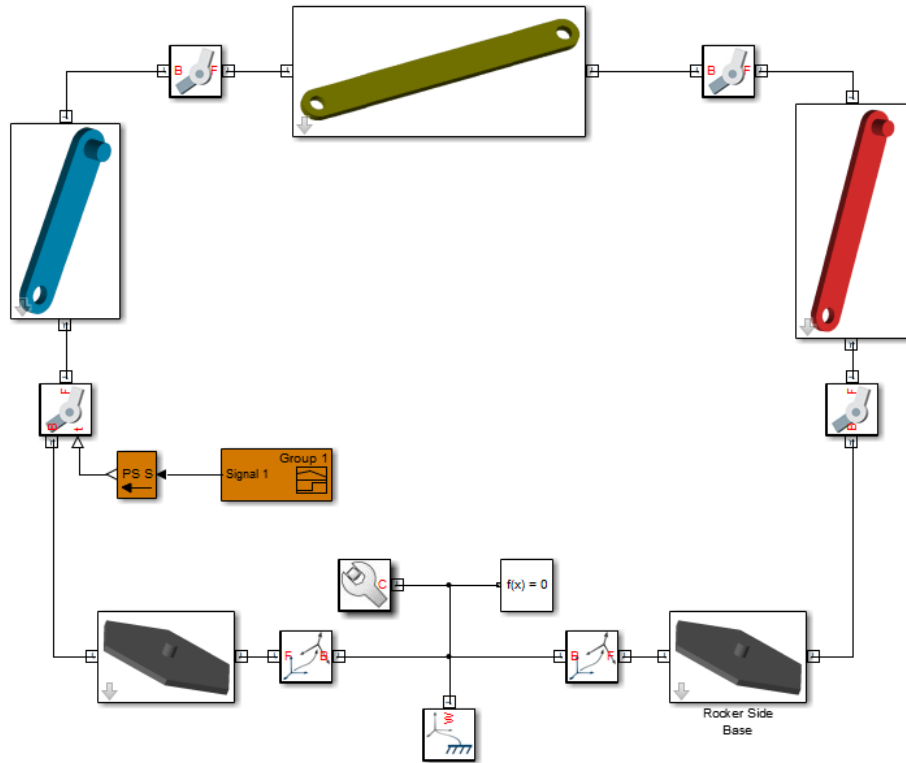
Applying Forces and Torques

You can actuate a model by applying a force or torque to a rigid body or to a joint. To represent forces and torques acting on a rigid body, SimMechanics provides a Forces and Torques library. Drag a block from this library and connect it to the rigid body frame(s) that you want to apply the force or torque to.

One block represents an external force or torque—External Force and Torque. The other blocks represent internal forces between two rigid body frames. You can represent a general internal force, using the Internal Force block, or a specific internal force type, using Spring and Damper Force and Inverse Square Law Force blocks. The figure shows how you can use the External Force block to actuate the crank link of the four-bar model.

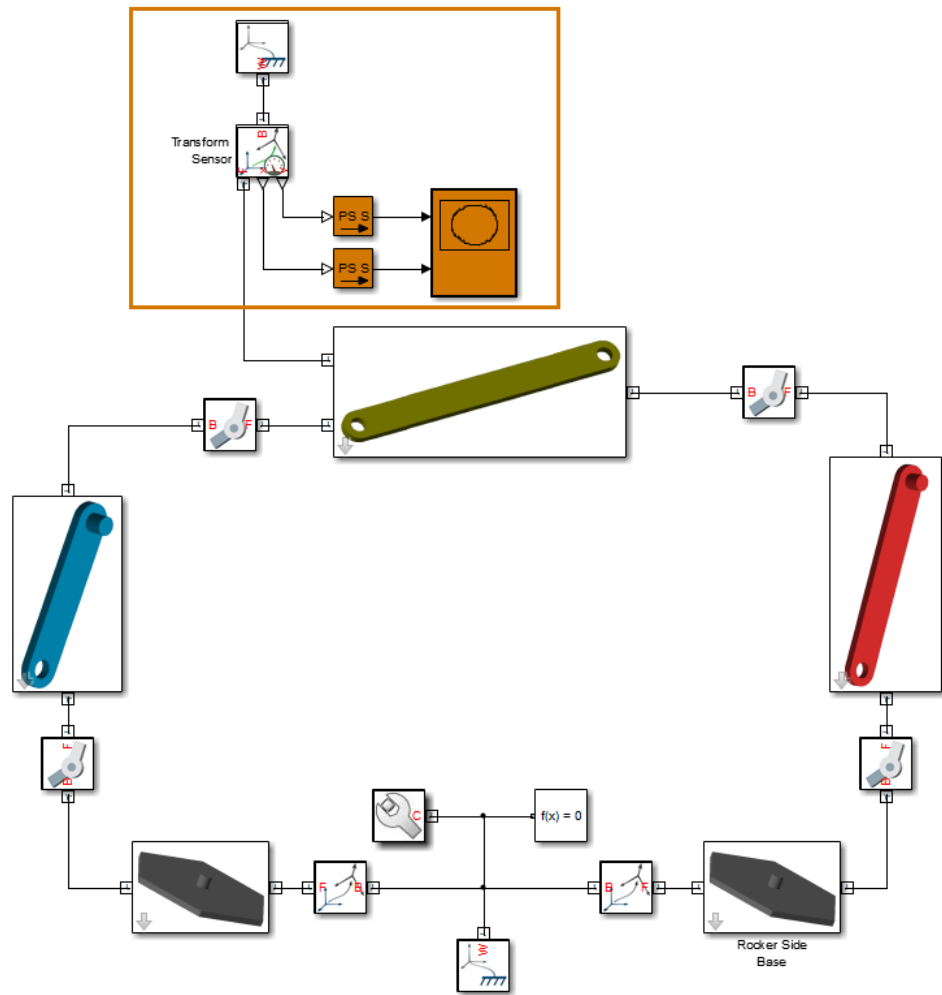


To represent forces and torques acting at a joint, SimMechanics provides a selection of actuation inputs in each Joint block. Each joint primitive—the basic component of a joint block—provides a selection of actuation inputs that you can select. You can represent a torque acting on a revolute or spherical joint primitive, or a force acting on a prismatic joint primitive. The figure shows how you can use the base-crank revolute joint block to actuate the joint directly.



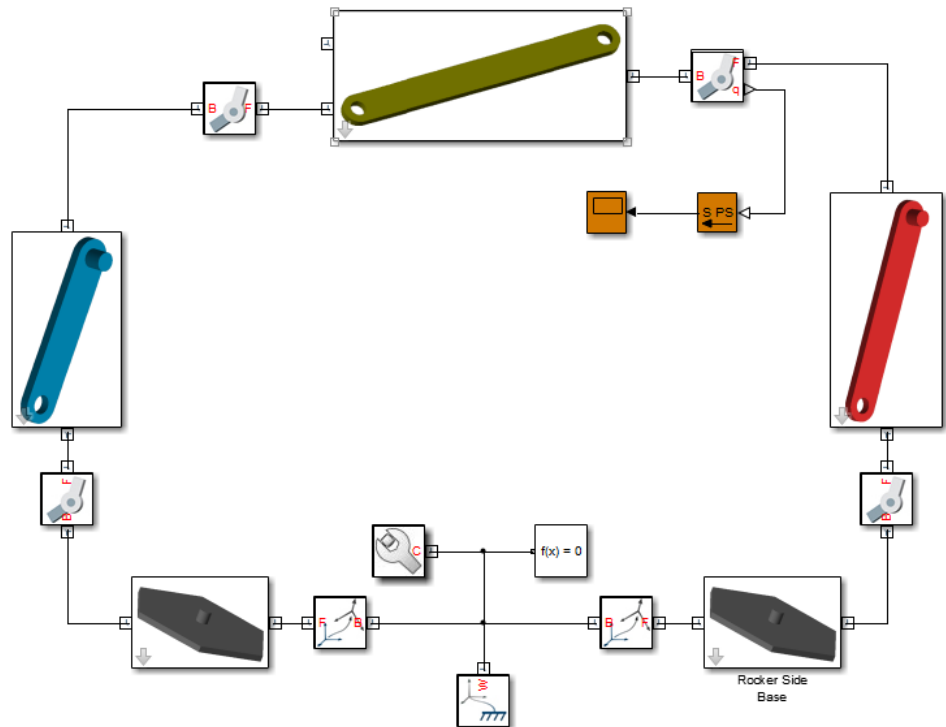
Sensing Motion

You can sense motion between two arbitrary rigid body frames. For this task, SimMechanics provides the Transform Sensor block, which you find in the Frames and Transforms library. This block provides the broadest motion sensing capability in SimMechanics. With it, you can sense position, velocity, and acceleration, both rotational and translational, between any two frames in a model. The figure shows how you can use the Transform Sensor block to sense the position coordinates of the coupler link reference frame with respect to the World frame.



To sense motion directly between two rigid body frames connected at a joint, SimMechanics provides a selection of sensing outputs in each joint block. Each joint primitive provides a selection of sensing outputs that you can select. You can sense rotational position, velocity, and acceleration using revolute and spherical joint primitives. You can also sense translational position, velocity, and acceleration using prismatic joint primitives. The

figure shows how you can sense the angular position of the coupler-rocker revolute joint directly from the joint block.



Related Examples

- “Model Simple Link” on page 1-32
- “Model Pendulum” on page 1-37

Concepts

- “Multibody Modeling Workflow” on page 1-16

Multibody Modeling Workflow

In this section...
“Model Rigid Bodies” on page 1-16
“Assemble Multibody Model” on page 1-21
“Add Forces, Torques, and Motion Sensors” on page 1-24
“Simulate and Analyze model” on page 1-28

The multibody modeling process contains a set of well-defined, sequential steps. Before you begin, define the intent of the model. Then, select a modeling approach and define the model requirements.

SimMechanics supports two modeling approaches:

- Manually build model — most common modeling approach. The following sections outline the manual approach.
- Automatically generate model from CAD assembly — for users wishing to simulate a CAD assembly in a physical modeling environment. Approach requires access to supported CAD software and assembly files. See “CAD Translation”.

Model Rigid Bodies

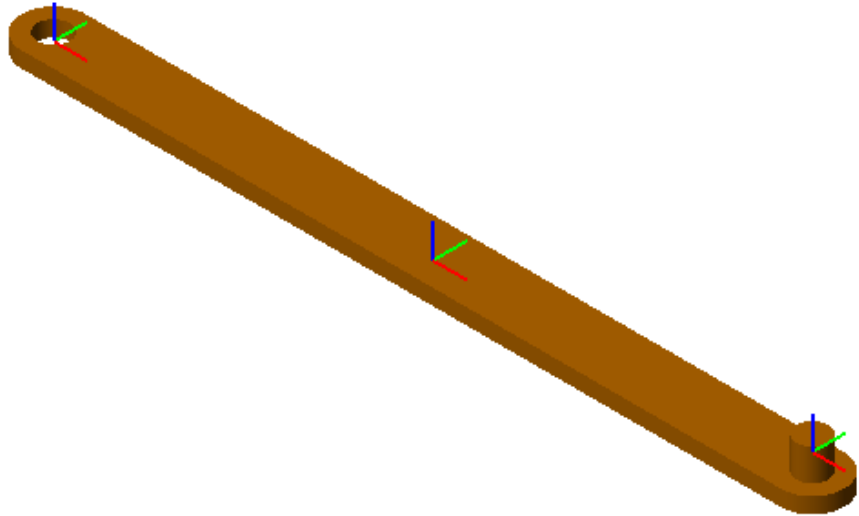
Rigid bodies are the building blocks of a multibody system. Before you can connect rigid bodies with joints and constraints, you must model the rigid bodies. You can create two types of rigid bodies:

- Simple — Use a single Solid block to model the rigid body. Simple rigid bodies are quicker to model. Use simple rigid bodies to quickly produce proof-of-concept models, before you create more detailed rigid body subsystems.

A simple cylinder is a simple rigid body.



- Compound — Rigidly connect multiple Solid blocks to model the rigid body. Compound rigid bodies require more time to model, but provide the most accurate representation of a rigid body that you can manually build.
A detailed binary link is a compound rigid body.



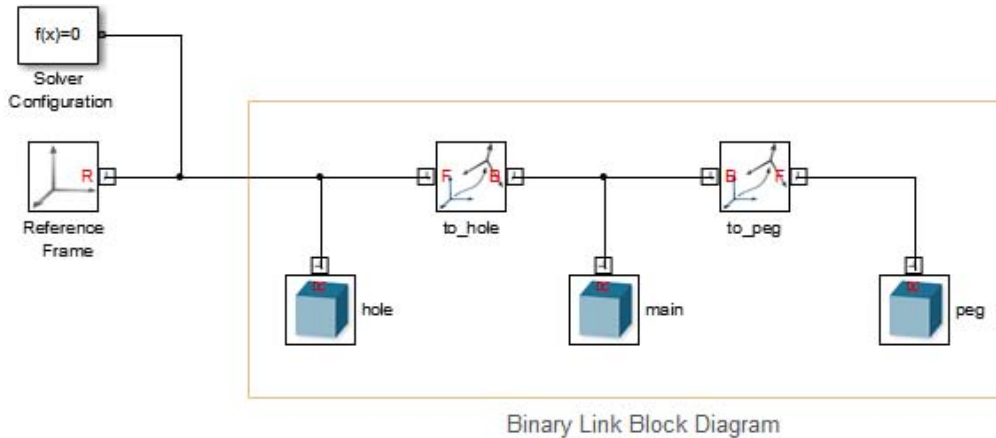
A complete rigid body subsystem contains the following:

- Frames — Construct with position and orientation in space.
- Physical properties — Geometry, inertia, and graphic parameters of a solid.

Add Frames

To add frames to a rigid body subsystem, you use the Rigid Transform block. The block rotates and/or translates a base frame to obtain a follower frame. A chain of Rigid Transform blocks represents a chain of frames. Connect the reference frame port of a Solid block to a frame port or line to give the frame a position and orientation in space. See “Representing Frames”.

The binary link subsystem contains three Solid blocks rigidly connected with two Rigid Transform blocks. Each Rigid Transform block translates a local reference frame, located at the center of the link, by an amount equal to half the link length along the length axis. The two end frames serve as joint connection frames.



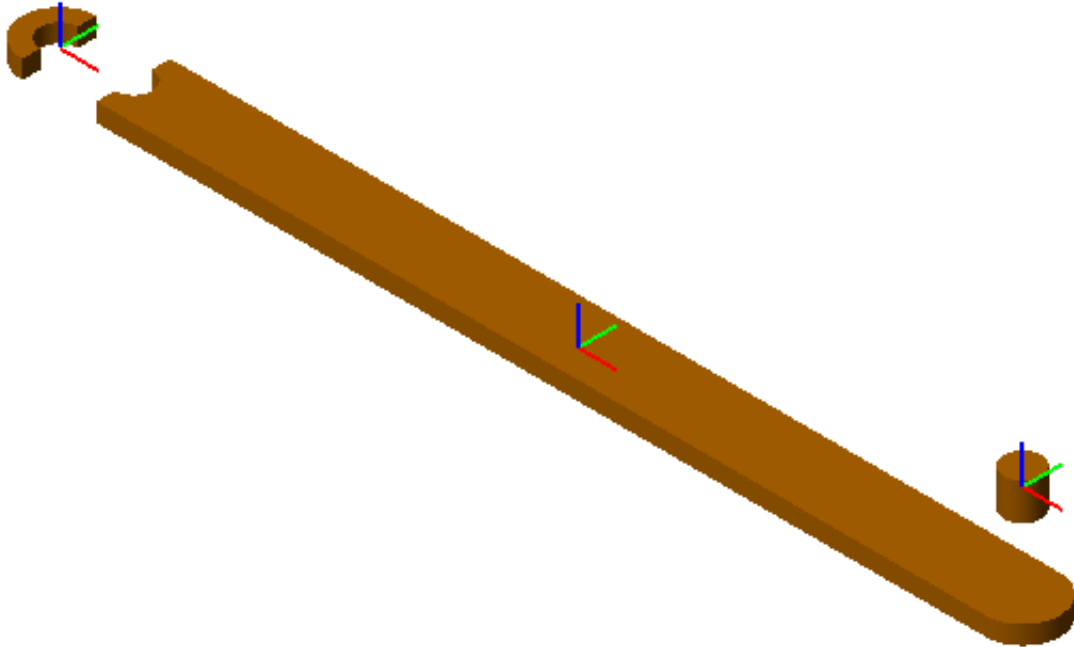
Add Geometry, Inertia, and Graphic Properties

To add geometry, inertia, and graphic properties to a rigid body, you use the Solid block. In the dialog box of the block, you can specify the numerical values for each parameter set:

- Geometry — 3-D shape of the rigid body. Required for assembly, visualization and simulation.
- Inertia — Mass or density and inertia tensor. Required for simulation.
- Graphic — Color of the rigid body. Required for visualization.

In the binary link subsystem, three Solid blocks provide the physical properties of three elementary pieces:

- Peg — Cylinder shape
- Main body — General Extrusion shape
- Hole Section — general Extrusion shape



In the Inertia menu of the Solid dialog box, you can specify the density of the link material — e.g. 2.70 g/cm^3 for Aluminum. SimMechanics provides the option to automatically calculate the moments and products of inertia from geometry. To provide a uniform density to the binary link, the three Solid blocks contain the same value in the **Density** field.

In the Graphic menu of the Solid dialog box, you can specify the color of the link material. In this example, the color is orange with RGB vector $[0.8 \ 0.45 \ 0]$. To provide a single color to the binary link, the three Solid blocks contain the same RGB vector in the **Color** parameter.

Assemble Multibody Model

Once you have created the rigid body subsystems, you can assemble the subsystems into a mechanism or machine. In a mechanism or machine, joints and constraints provide well-defined degrees of freedom that constrain rigid body motion. Two types of motion are possible:

- Rotation about one or more axes
- Translation along one or more axes

Connect Joints

To assemble rigid body subsystems into complete multibody systems, connect the with joints. SimMechanics provides a library with fourteen joint blocks. Each block provides a different number and/or type of mechanical degrees of freedom. Exactly two rigid body frames connect to each joint, with each frame belonging to a different rigid body.

Joints are composed of joint primitives — elementary joints that you can combine to create more complex joints. SimMechanics contains three joint primitives:

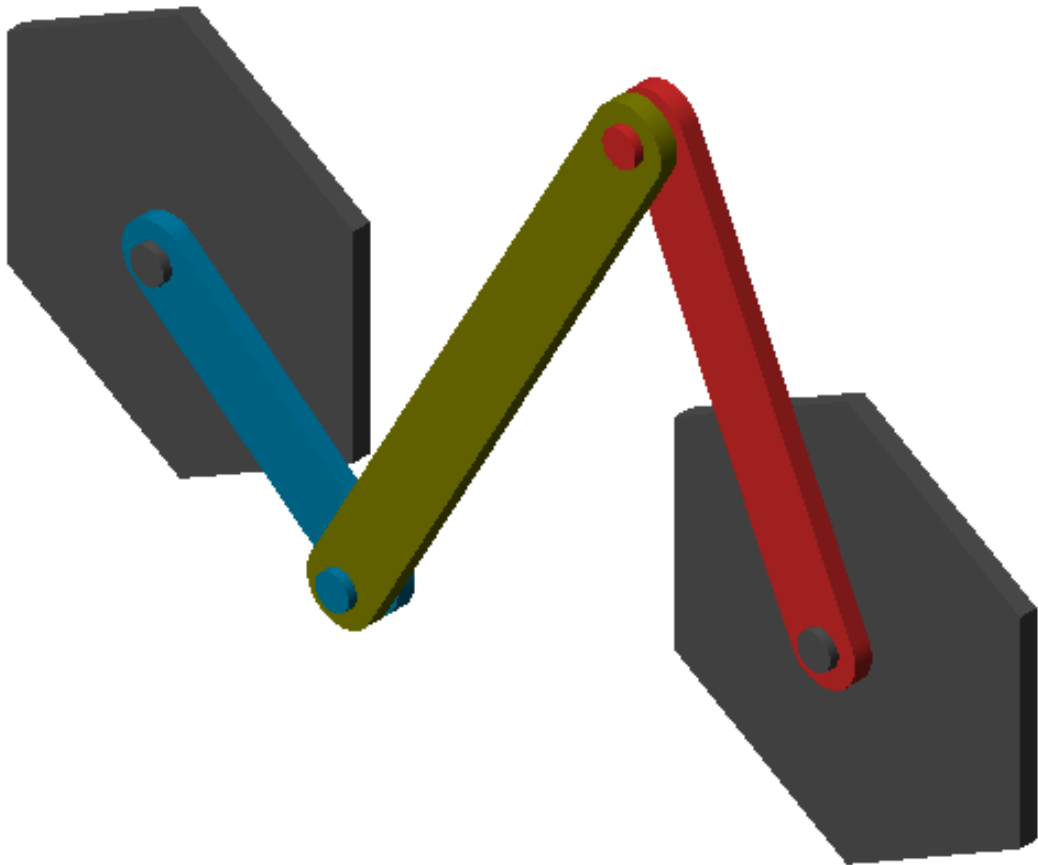
- Prismatic — one translational degree of freedom along an axis
- Revolute — one rotational degree of freedom about an axis
- Spherical — three concurrent degrees of freedom about three axes

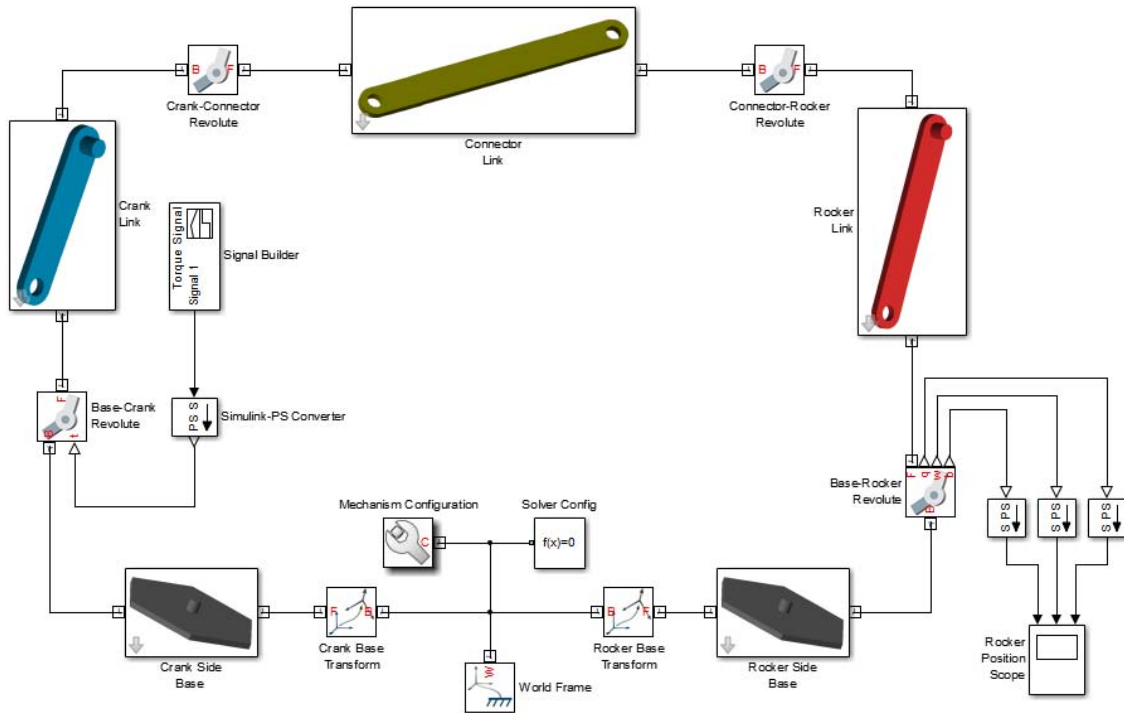
The following table identifies the joint primitives associated with each joint.

		Prismatic Primitives			
		0	1	2	3
Revolute Primitives	0	Weld Joint	Prismatic Joint	Rectangular Joint	Cartesian Joint
	1	Revolute Joint	Cylindrical Joint	Planar Joint	—

		Prismatic Primitives			
		0	1	2	3
	2	Universal Joint	—	—	—
	3	Gimbal Joint	Bearing Joint	—	6-DOF Joint
Spherical Primitives	1	Spherical Joint	Telescoping Joint	—	Bushing Joint

The four-bar system contains four rigid bodies connected with four revolute joints. The block diagram for this model contains four rigid body subsystems connected with four Revolute Joint blocks. The following figures show the Mechanics Explorer display of a four-bar model and the associated block diagram.





Specify Joint State Targets

To specify the initial configuration of a multibody assembly, use the **State Targets** menu of the joint dialog box. You can specify values for the initial joint position and velocity, and assign different priorities for the state targets. SimMechanics attempts to meet the state target. If the state targets make assembly impossible, SimMechanics tries to use an approximate value that allows assembly.

Add Forces, Torques, and Motion Sensors

You can add force and torques to, or between, rigid body frames. The following table summarizes the force/torque types that you can add to a model. The

Procedure column identifies the steps required to add each force/torque type to a model.

Force/Torque Type	Description	Procedure
Joint actuation	Force or torque between base and follower frames along or about joint primitive axis	<ol style="list-style-type: none"> 1 In the Actuation menu of the joint dialog box, select the desired actuation mode. 2 Connect a physical signal line to each exposed physical signal port.
Joint internal mechanics	Spring and damper force or torque between base and follower frames along or about joint primitive axis	<ol style="list-style-type: none"> 1 In the Internal Mechanics menu of joint dialog box, enter the spring and damper parameters for the joint.
Rigid body actuation	Force or torque acting on a rigid body frame not connected to a joint	<ol style="list-style-type: none"> 1 Connect an External Force and Torque block to the rigid body frame you wish to actuate. 2 In the dialog box of the block, select the force and torque components you wish to specify and the frame in which you wish to resolve the components.

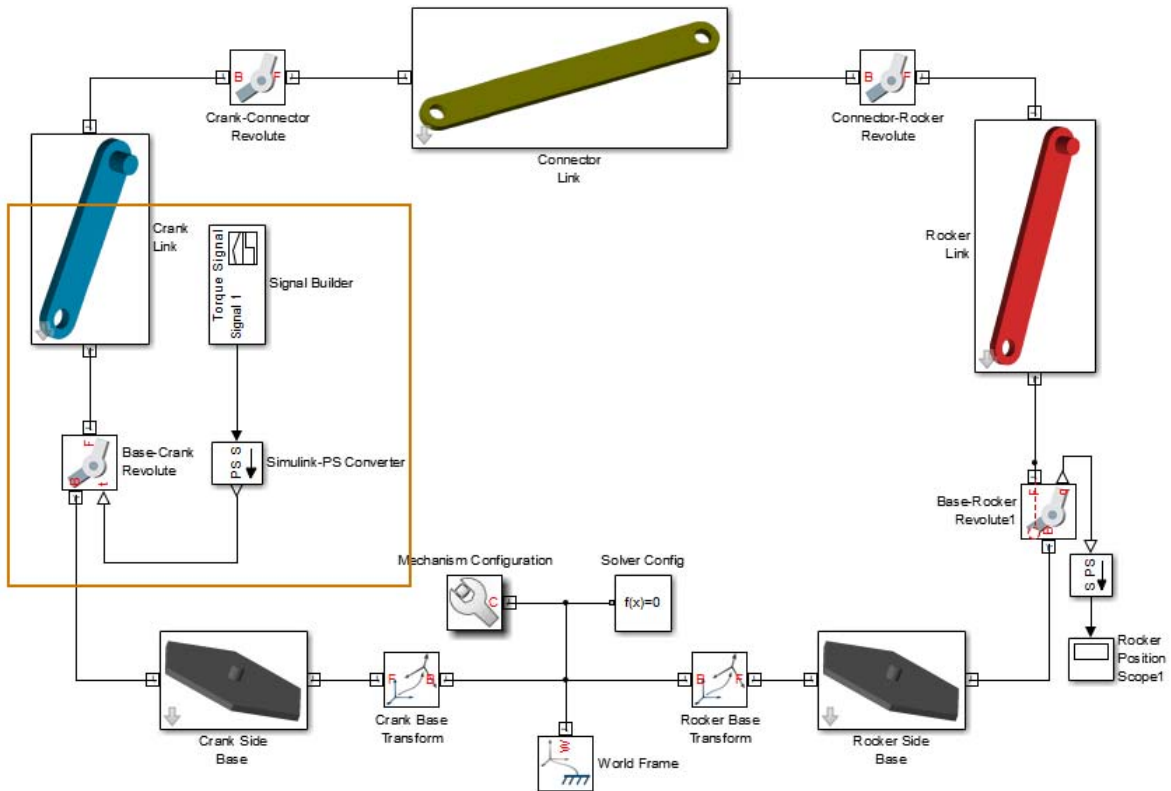
Force/Torque Type	Description	Procedure
		<ol style="list-style-type: none"> 3 Connect a physical signal line to each exposed physical signal port.
Rigid Body Internal Forces	Force acting between two rigid body frames, one frame per rigid body	<ol style="list-style-type: none"> 1 Connect the Inverse Square Law Force or Spring and Damper Force block between the two rigid body frames. 2 In the dialog box of the block, enter the force constants.

You can also add mechanical sensing between frames. Force sensing is limited Inverse Square Law Force or Spring and Damper Force blocks. The following table summarizes the types of motion and force sensing you can add to a model. The **Procedure** column identifies the steps required to add each sensing type to a model.

Sensing	Description	Procedure
Joint Motion	Sensing of position, velocity, and acceleration parameters of joint follower frame with respect to base frame	<ol style="list-style-type: none"> 1 In the Sensing menu of the joint dialog box, select the desired motion parameter. 2 Connect a physical signal to each exposed physical signal port.
Rigid Body Motion	Sensing of position, velocity, and	<ol style="list-style-type: none"> 1 Connect the Transform Sensor

Sensing	Description	Procedure
	acceleration parameters of one rigid body frame with respect to any other frame in a model	<p>block to two rigid body frames.</p> <ol style="list-style-type: none"> 2 In the dialog box of the Transform Sensor block, select the motion parameters you wish to sense. 3 Connect a physical signal to each exposed physical signal port.
Force Input	Sensing of force magnitude in Inverse Square Law Force and Spring and Damper Force blocks	<ol style="list-style-type: none"> 1 In the dialog box of the force block, select Sense Force. 2 Connect physical signal to the exposed fm physical signal port.

The following figure shows an application of joint actuation inputs. The Base-Crank joint of a four-bar model receives a torque input indirectly from the Simulink block Signal Builder. The Simulink-PS Converter block converts the Simulink signal into a physical signal compatible with SimMechanics blocks.



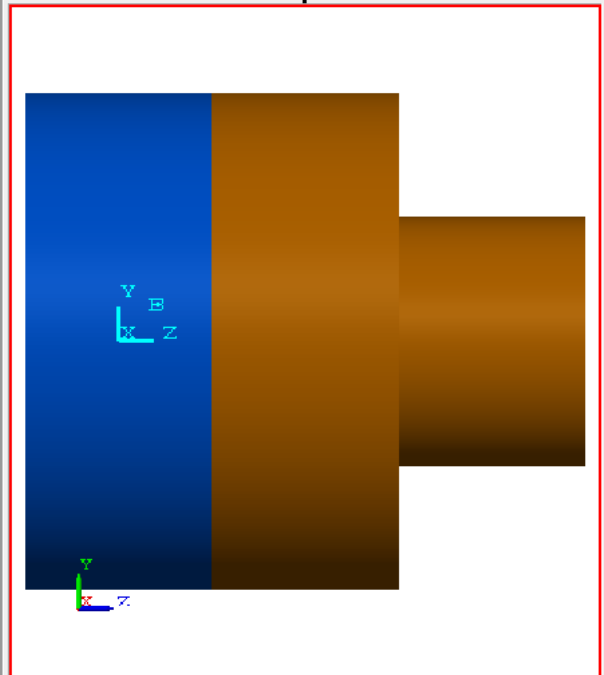
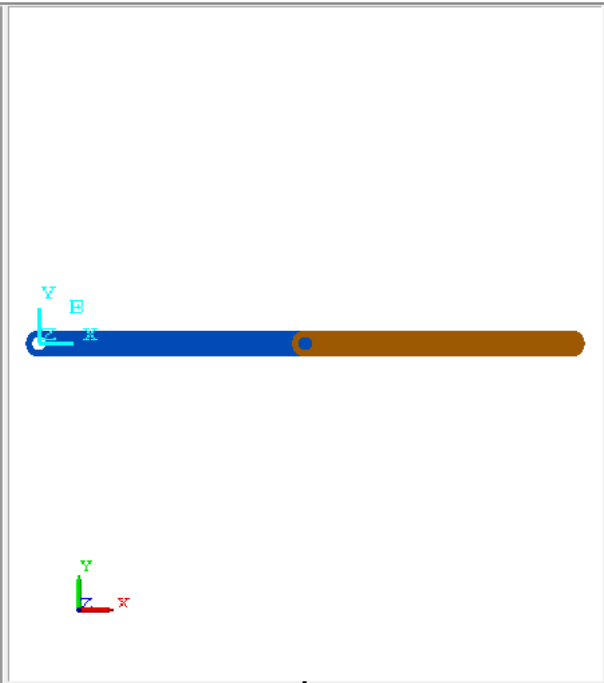
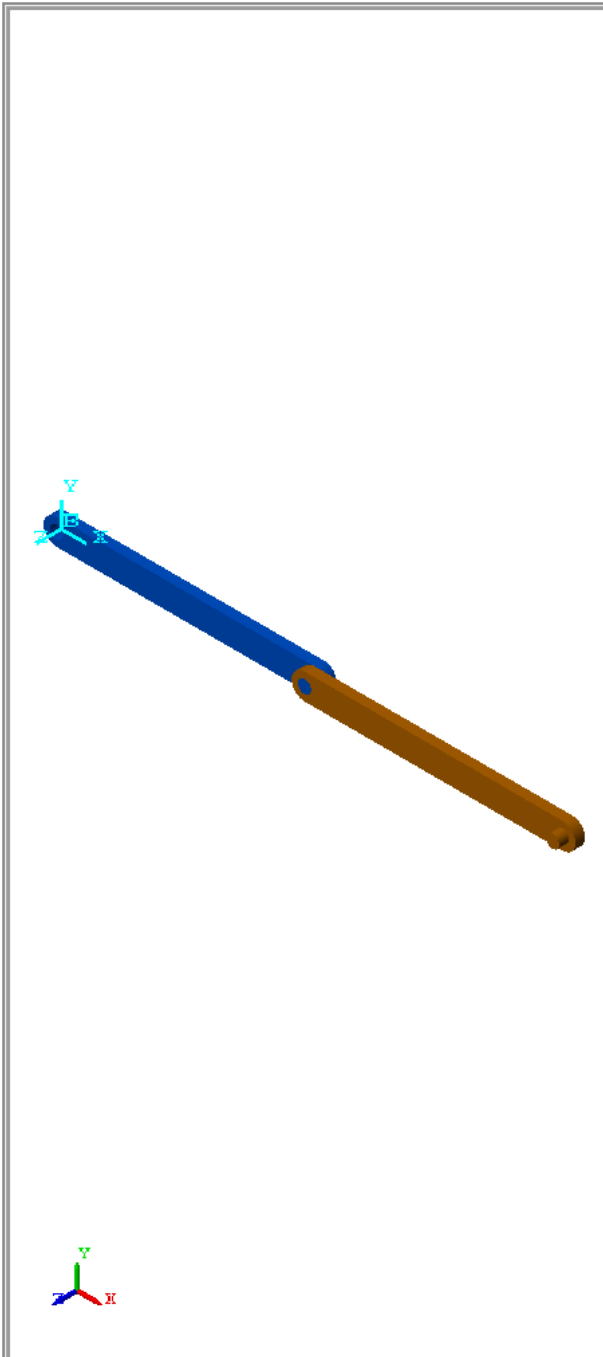
Simulate and Analyze model

Run the simulation to examine the dynamic behavior of the model. Simulink provides a set of model simulation options that you can adjust for your application. Before running simulation:

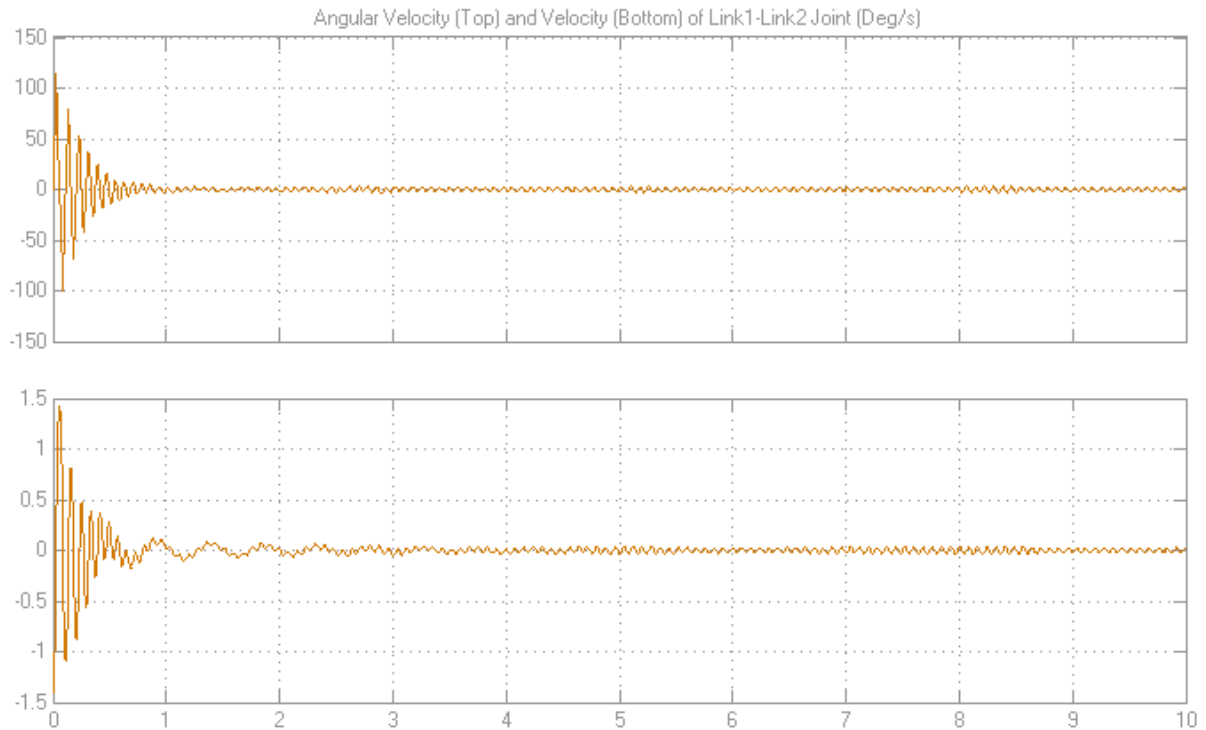
- Check the choice of solver. SimMechanics models require a continuous solver. Variable-step solvers provide the best performance. Use ode45 (Dormand-Prince) as a first try for most models.

- Check the solver step sizes and tolerances. Smaller values for both parameters produce more accurate results at the cost of increased simulation time.
- Check the simulation time span. To let a simulation run indefinitely, specify `inf` in the **Stop time** field.

The Mechanics Explorer utility provides 3-D visualization for SimMechanics models. By default, the utility opens the first time you update a model, and refreshes for all subsequent model updates. The following figure shows the Mechanics Explorer display of a double-pendulum model.



During simulation, you can open any scope blocks in the model to examine the dynamic behavior of the model. The following figure shows the angular position and velocity of the bottom frame of a damped double-pendulum model as functions of time.

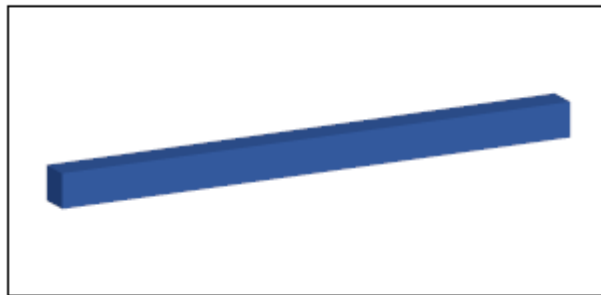


Model Simple Link

In this section...
“Model Overview” on page 1-32
“Build Model” on page 1-33
“Generate Subsystem” on page 1-34
“Visualize Model” on page 1-35
“Save Model” on page 1-36
“Model Simple Pendulum” on page 1-36

Model Overview

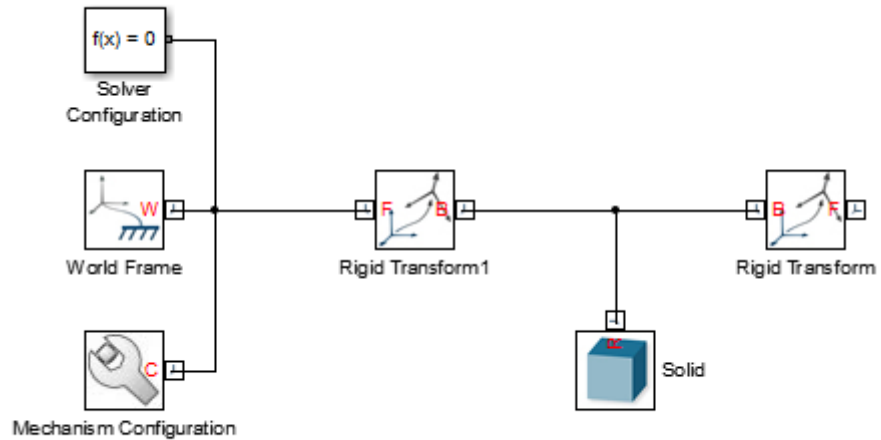
Mechanical links are common building blocks in linkages, mechanisms, and machines. The simple pendulum is an example with one link. In this tutorial, you model a simple link with two end frames that you can later connect to joints. Rigid Transform blocks provide the end frames, while a Solid block provides geometry, inertia, and color. For simplicity, the model assumes the link has a brick shape.



Build Model

- 1 At the MATLAB command line, enter `smnew`. The SimMechanics block library and a new model open up.
- 2 In the model, copy the Rigid Transform block and paste a copy in the model.
- 3 Delete these blocks: Simulink-PS Converter, PS-Simulink Converter, and Scope.
- 4 Connect the blocks as shown in the figure.

Note The base (B) frame ports of both Rigid Transform blocks must face the Solid block.



- 5 In the dialog box for the Solid block, specify these parameters.

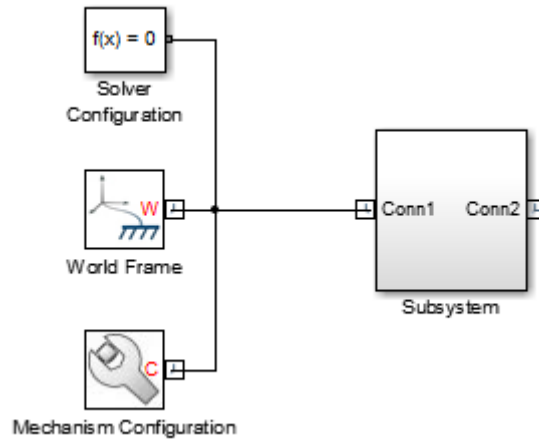
Parameter	Value
Geometry > Dimensions	[L W H] cm
Inertia > Density	rho kg/m ³
Graphic > Visual Properties > Color	rgb


6 In the dialog boxes for the Rigid Transform blocks, specify these parameters.

Parameter	Rigid Transform 1	Rigid Transform
Translation > Method	Standard Axis	Standard Axis
Translation > Axis	-X	+X
Translation > Offset	L/2 cm	L/2 cm

Generate Subsystem

- 1 Select the Solid block and the two Rigid Transform blocks.
- 2 Press **Ctrl+G** to enclose the blocks in a subsystem.




- 3** Click the Subsystem block and press **Ctrl+M** to create a subsystem mask.
- 4** In the **Parameters & Dialog** tab of the Mask Editor window, drag edit boxes  inside the **Parameters** group and specify the following parameters.

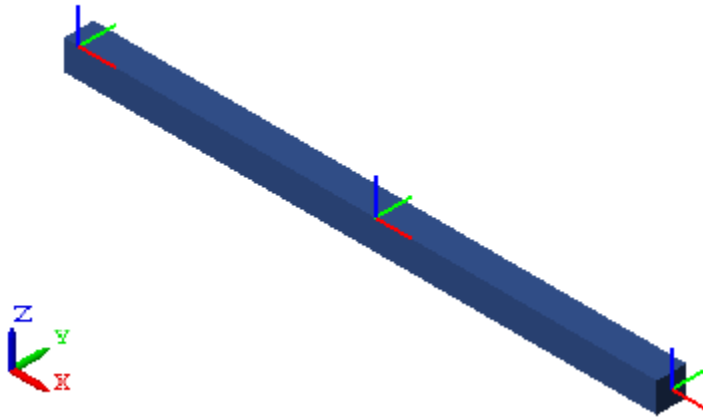
Prompt	Name
Length (cm):	L
Width (cm):	W
Thickness (cm):	H
Density (kg/m ³):	rho
Color [R G B]:	rgb

- 5** In the Subsystem block dialog box, specify these parameters.

Parameter	Value
Length (cm):	20
Width (cm):	1
Thickness (cm):	1
Density (cm):	2700
Color [R G B]:	[0.25 0.40 0.70]

Visualize Model

In the model window, press **Ctrl+D**. Mechanics Explorer opens with a 3-D display of the simple link. In the Mechanics Explorer toolstrip, click the isometric view button  to see the 3-D view.



Save Model

To use it in later tutorials, save the link subsystem as a custom library block. Name the block Link, and then drag it to a custom library in a convenient folder.

Model Simple Pendulum

Using the link block, you can model a simple pendulum. See “Model Pendulum” on page 1-37.

Model Pendulum

In this section...

“Model Overview” on page 1-37

“Build Model” on page 1-38

“Specify Gravity” on page 1-39

“Add Motion Sensing” on page 1-40

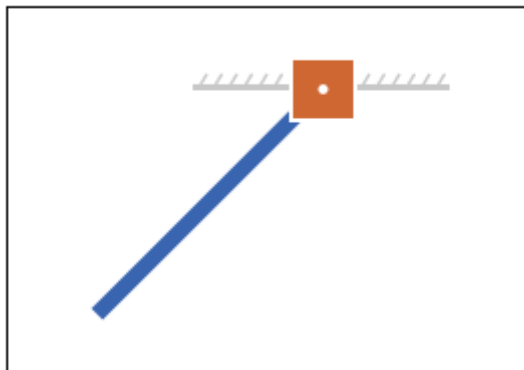
“Guide Model Assembly” on page 1-41

“Assemble and Simulate Model” on page 1-41

“Save Model” on page 1-43

Model Overview

The pendulum is the simplest mechanical system you can model. This system contains two rigid bodies, a link and a fixed pivot, connected by a revolute joint. In this tutorial, you model and simulate this system using the custom link block you created in “Model Simple Link” on page 1-32. A Revolute Joint block represents the joint connecting the link to the fixed pivot.



Build Model

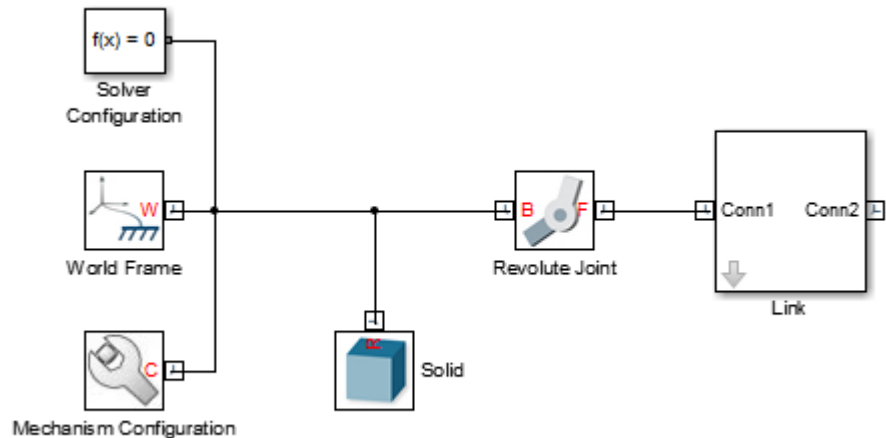
- 1** At the MATLAB command line, enter `smnew`. The SimMechanics block library and a new model open up.
- 2** In the model, delete all blocks except Solver Configuration, World Frame, and Mechanism Configuration.
- 3** Drag the custom Link block into the model.

This is the block you created in the tutorial “Model Simple Link” on page 1-32.

- 4** Drag the following SimMechanics blocks into the model.

Block	Library	Quantity
Revolute Joint	SimMechanics Second Generation (SM 2G) > Joints	1
Solid	SimMechanics Second Generation (SM 2G) > Body Elements	1

- 5** Connect the blocks as shown in the figure.



- 6 In the Solid block dialog box, specify these parameters.

Parameter	Value
Geometry > Dimensions	[4 4 4] cm
Graphic > Visual Properties > Color	[0.80 0.45 0]

Specify Gravity

The Revolute Joint block sets the common Z axis of its base and follower frames as the rotation axis. To ensure gravity acts in an orthogonal direction to the rotation axis, you must change the gravity vector. In this procedure, you specify gravity so it acts along the -Y axis.

- 1 Double-click the Mechanism Configuration block.
- 2 In **Gravity**, enter [0 -9.81 0] and click **OK**.

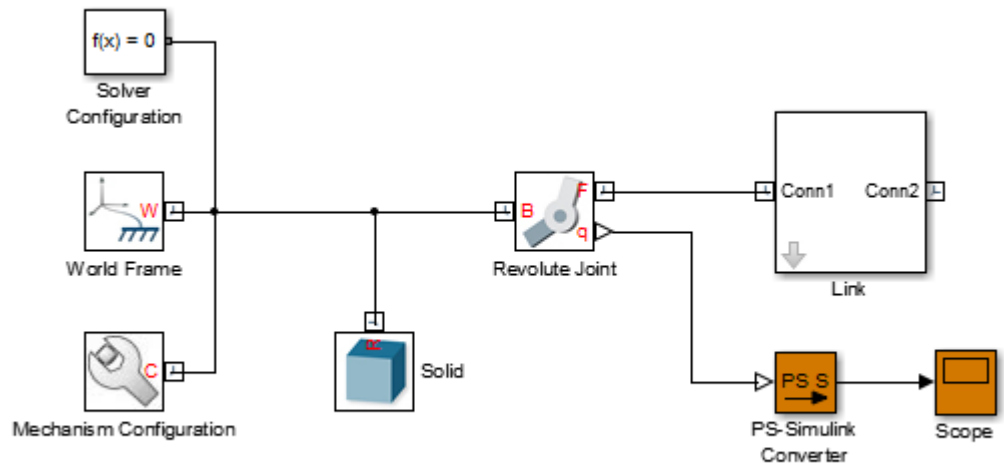
Add Motion Sensing

For model analysis, you can sense joint motion directly from the joint block. In this procedure, you sense the angular position of the joint. This position is the angle of the joint follower frame with respect to the base frame.

- 1 Double-click the Revolute Joint block.
- 2 Select **Sensing > Position** and click **OK**.
- 3 Drag the following blocks into the model.

Block	Library	Quantity
PS-Simulink Converter	Simscape > Utilities	1
Scope	Simulink > Sinks	1

- 4 Connect the blocks as shown in the figure.



Guide Model Assembly

Set the initial angle at the revolute joint between the link and the fixed pivot.

- 1 Double-click the Revolute Joint block.
- 2 Select **State Targets > Specify Position Target**.
- 3 In **Value**, enter -60 and click **OK**.

Assemble and Simulate Model

In the model window, press **Ctrl+D**. SimMechanics assembles the model in its initial configuration. Mechanics Explorer displays a 3-D view of this configuration with the Z axis pointing up. Since gravity acts along the -Y axis, it helps to change the view convention so the Y axis points up.

- 1 In Mechanics Explorer, set **View convention** to Y up (XY Front).

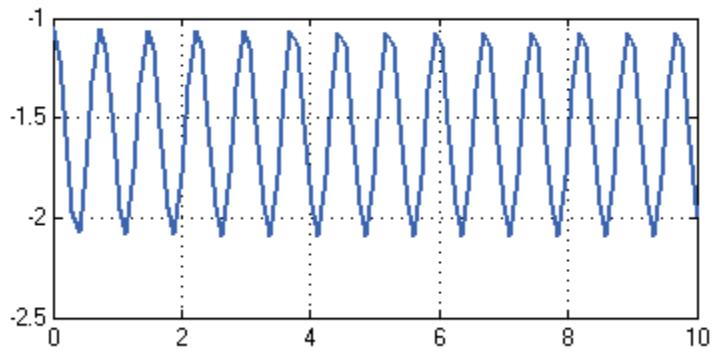
- 2 Click any of the view buttons  to refresh the viewpoint. The figure shows the pendulum model in the isometric view.



3 Simulate the model. Mechanics Explorer plays a 3-D animation of the model simulation.

4 Double-click the Scope block to analyze the angular position of the revolute joint.

The figure shows the angular position plot in radian units. Click the autoscale button to view the full plot.



Save Model

So that you can reuse the simple pendulum model, save it as `simple_pendulum` in a convenient folder.

Modeling with SimMechanics First and Second Generations

SimMechanics software contains two technologies: First Generation and Second Generation. First-generation technology includes the block library and visualization utility found in SimMechanics releases prior to R2012a. Second-generation technology introduces a simpler modeling paradigm with a new block library, a powerful computational engine, an advanced visualization utility based on OpenGL computer graphics, and tighter integration with Simscape products.

SimMechanics first- and second-generation technologies have different sets of capabilities. Which technology to use depends on the effects you need to model. Use first-generation technology for models requiring variable gravity, certain complex constraints, or to measure reaction or constraint forces. In nearly all other cases, use second-generation technology.

The table provides a detailed comparison between first- and second-generation technologies.

Feature	SimMechanics First Generation	SimMechanics Second Generation
Mass/Inertia Calculation	Manual only	Automatic or manual
Solid Geometry	No	Yes
Animation Replay	No	Yes
3-D Model Exploration	Limited	Yes
Initial State Targets	Limited	Yes
Simscape Logging	No	Yes
Code Generation	Yes	Yes
CAD Import	Yes	Yes ²
Motion Actuation	Yes	Yes
Force/Torque Sensing	Yes	Yes ³
Complex Constraints ¹	Yes	Gears only
Variable Mass/Gravity	Yes	No

¹Point-curve, Gear, Velocity, and Screw constraints

²CAD update supported only in SimMechanics First Generation

³Actuation forces/torques only

SimMechanics continues to support first-generation technology. You can maintain and simulate legacy models built with first-generation blocks. You also can still create a new first-generation model using the SimMechanics First Generation block library.