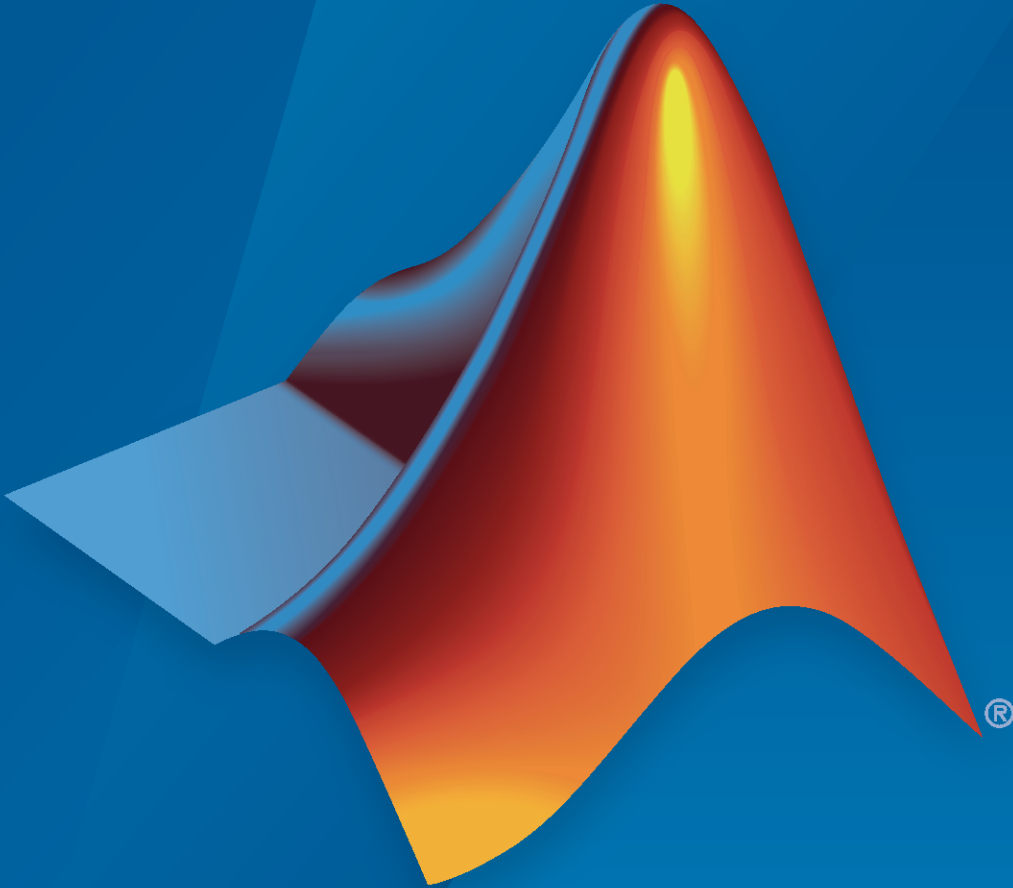


Powertrain Blockset™

Reference



MATLAB® & SIMULINK®

R2022b



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Powertrain Blockset™ Reference

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Revision History

October 2016	Online only	New for Version 1.0 (Release 2016b+)
March 2017	Online only	Revised for Version 1.1 (Release 2017a)
September 2017	Online only	Revised for Version 1.2 (Release 2017b)
March 2018	Online only	Revised for Version 1.3 (Release 2018a)
September 2018	Online only	Revised for Version 1.4 (Release 2018b)
March 2019	Online only	Revised for Version 1.5 (Release 2019a)
September 2019	Online only	Revised for Version 1.6 (Release 2019b)
March 2020	Online only	Revised for Version 1.7 (Release 2020a)
September 2020	Online only	Revised for Version 1.8 (Release 2020b)
March 2021	Online only	Revised for Version 1.9 (Release 2021a)
September 2021	Online only	Revised for Version 1.10 (Release 2021b)
March 2022	Online only	Revised for Version 1.11 (Release 2022a)
September 2022	Online only	Revised for Version 1.12 (Release 2022b)

1	<u>Drivetrain Blocks</u>
2	<u>Vehicle Dynamics Blocks</u>
3	<u>Energy Storage Blocks</u>
4	<u>Propulsion Blocks</u>
5	<u>Electric Motor, Converters, Inverter Blocks</u>
6	<u>Scenario Creation Blocks</u>
7	<u>Transmission Blocks</u>
8	<u>Functions</u>
9	<u>Apps</u>

Drivetrain Blocks

Rotational Inertia

Ideal mechanical rotational inertia

Library: Powertrain Blockset / Drivetrain / Couplings
 Vehicle Dynamics Blockset / Powertrain / Drivetrain / Couplings



Description

The Rotational Inertia block implements an ideal mechanical rotational inertia.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrR	Mechanical power from base shaft	P_{TR}	$P_{TR} = T_R\omega$
		PwrC	Mechanical power from follower shaft	P_{TC}	$P_{TC} = T_C\omega$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrDampLoss	Power loss due to damping	P_d	$P_d = -b \omega ^2$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredShft	Rate change of stored internal torsional energy	P_s	$P_s = \omega\dot{\omega}J$

The equations use these variables.

T_R	Input torque
T_C	Output torque
ω	Driveshaft angular velocity
J	Rotational inertia
b	Rotational viscous damping
P_d	Power loss due to damping
P_s	Rate change of stored internal torsional energy

Ports

Input

RTrq — Input torque

scalar

Applied input driveshaft torque, T_R , in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

CTrq — Output torque

scalar

Load driveshaft torque, T_C , in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

R — Angular velocity and torque

two-way connector port

Angular velocity in rad/s. Torque is in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Two-way connection.

Inertia — Input

scalar

Rotational inertia, in kg·m².

Dependencies

To create the Inertia port, select **External inertia input**.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
Trq	R	Applied input driveshaft torque	T_R	N·m	
	C	Output driveshaft torque	T_C	N·m	
	Damp	Damping torque	$T_d=b\omega$	N·m	
Spd		Angular driveshaft speed	ω	rad/s	
PwrInfo	PwrTrnsfrd	PwrR	Mechanical power from base shaft	P_{TR}	W
		PwrC	Mechanical power from follower shaft	P_{TC}	W
	PwrNotTrnsfrd	PwrDampLoss	Power loss due to damping	P_d	W
	PwrStored	PwrStoredShft	Rate change of stored internal torsional energy	P_s	W

Dependencies

To enable this port, select **Output Info bus**.

Spd — Driveshaft speed

scalar

Angular driveshaft speed, ω , in rad/s.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

C — Angular velocity and torque

two-way connector port

Angular velocity in rad/s. Torque is in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Two-way connection.

Parameters

Block Options

Port Configuration — Specify configuration

Simulink (default) | Two-way connection

Specify the port configuration.

Dependencies

Specifying Simulink creates these ports:

- RTrq
- CTrq
- Spd

Specifying `Two-way` connection creates these ports:

- R
- C

Output Info bus – Selection

off (default) | on

Select to create the Info output port.

External inertia input – Input rotational inertia

off (default) | on

Dependencies

To create the Inertia port, select **External inertia input**.

Parameters

Rotational inertia, J – Inertia

.01 (default) | scalar

Rotational inertia, in $\text{kg}\cdot\text{m}^2$.

Dependencies

To enable this parameter, clear **Input rotational inertia**.

Torsional damping, b – Damping

.001 (default) | scalar

Torsional damping, in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Initial velocity, omega_o – Angular

0 (default) | scalar

Initial angular velocity, in rad/s .

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

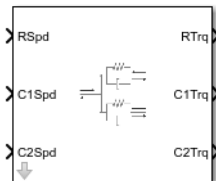
See Also

Split Torsional Compliance | Torsional Compliance

Split Torsional Compliance

Split torsional coupler

Library: Powertrain Blockset / Drivetrain / Couplings
 Vehicle Dynamics Blockset / Powertrain / Drivetrain / Couplings



Description

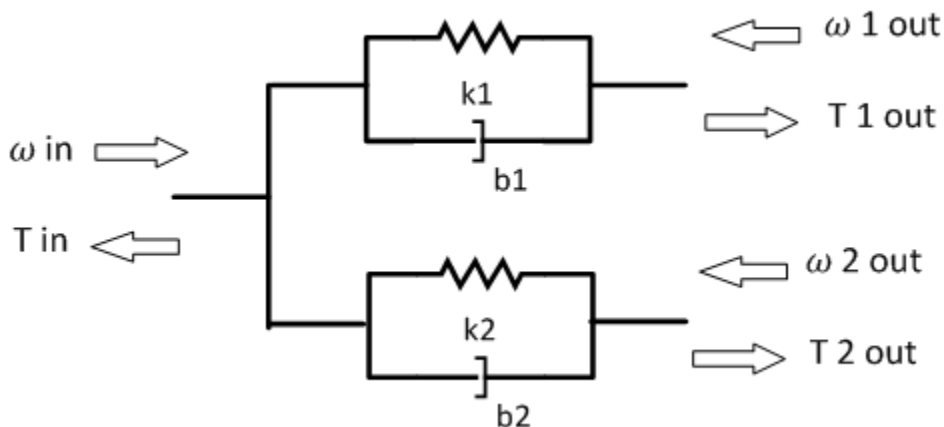
The Split Torsional Compliance block implements parallel spring-damper coupling between shafts. You can specify the type of coupling by selecting one of the **Coupling Configuration** parameters:

- Shaft split — Single input shaft coupled to two output shafts
- Shaft merge — Two input shafts coupled to a single output shaft

In fuel economy and emissions studies, you can use the Split Torsional Compliance block to model mechanical rotational compliance between common driveline elements such as motors, planetary gears, and clutches. For example, use the Shaft split configuration to couple a motor and two planetary gear sets. Use the Shaft merge configuration to couple a dual clutch transmission to an output shaft.

Shaft Split

For the Shaft split configuration, the block implements this schematic and equations.



$$T_{in} = -(\omega_{in} - \omega_{1out})b_1 - (\omega_{in} - \omega_{2out})b_2 - \theta_1 k_1 - \theta_2 k_2$$

$$T_{1out} = (\omega_{in} - \omega_{1out})b_1 + \theta_1 k_1$$

$$T_{2out} = (\omega_{in} - \omega_{2out})b_2 + \theta_2 k_2$$

$$\dot{\theta}_1 = (\omega_{in} - \omega_{1out})$$

$$\dot{\theta}_2 = (\omega_{in} - \omega_{2out})$$

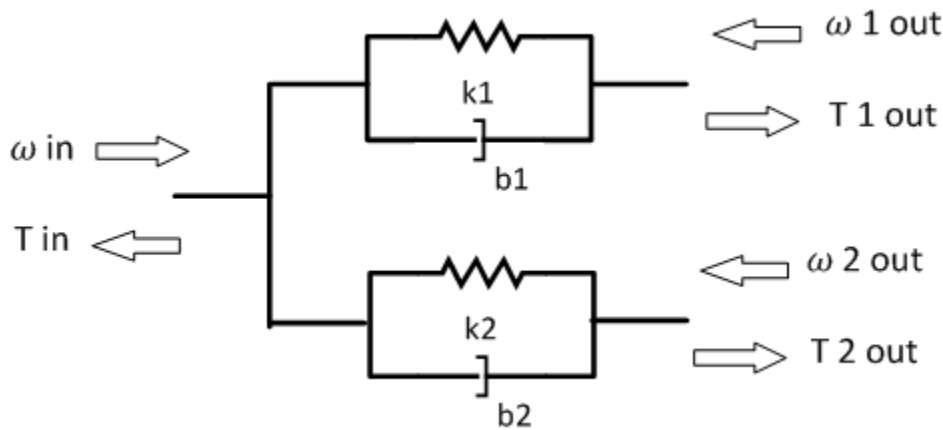
To account for frequency-dependent damping, both damping terms incorporate a low-pass filter.

The equations use these variables.

T_{in}	Resulting applied input reaction torque
ω_{in}	Input shaft rotational velocity
T_{1out}	Resulting applied torque to first output shaft
ω_{1out}	First output shaft rotational velocity
T_{2out}	Resulting applied torque to second output shaft
ω_{2out}	Second output shaft rotational velocity
θ_1, θ_2	First, second shaft rotation, respectively
b_1, b_2	First, second shaft viscous damping, respectively
k_1, k_2	First, second shaft torsional stiffness, respectively

Shaft Merge

For the Shaft merge configuration, the block implements this schematic and equations.



$$T_{out} = (-\omega_{out} + \omega_{1in})b_1 + (-\omega_{out} + \omega_{2in})b_2 + \theta_1 k_1 + \theta_2 k_2$$

$$T_{1out} = (\omega_{out} - \omega_{1in})b_1 - \theta_1 k_1$$

$$T_{2out} = (\omega_{out} - \omega_{2in})b_2 - \theta_2 k_2$$

$$\dot{\theta}_1 = (\omega_{1in} - \omega_{out})$$

$$\dot{\theta}_2 = (\omega_{2in} - \omega_{out})$$

To account for frequency-dependent damping, both damping terms incorporate a low-pass filter.

The equations use these variables.

T_{out}	Resulting applied output torque
ω_{out}	Output shaft rotational velocity
T_{1in}	Resulting reaction torque to first input shaft
ω_{1in}	First input shaft rotational velocity
T_{2in}	Resulting reaction torque to second input shaft
ω_{2in}	Second input shaft rotational velocity
θ_1, θ_2	First, second shaft rotation, respectively
b_1, b_2	First, second shaft viscous damping, respectively
k_1, k_2	First, second shaft torsional stiffness, respectively

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrR	For the Shaft split configuration, mechanical power from input shaft	$P_{TR} = -T_R\omega_R$
		PwrC1	For the Shaft split configuration, mechanical power from first output shaft	$P_{TC1} = -T_{C1}\omega_{C1}$
		PwrC2	For the Shaft split configuration, mechanical power from second output shaft	$P_{TC2} = -T_{C2}\omega_{C2}$
		PwrC	For the Shaft merge configuration, mechanical power from output shaft	$P_{TC} = T_C\omega_C$

Bus Signal		Description	Variable	Equations
	PwrR1	For the Shaft merge configuration, mechanical power from first input shaft	P_{TR1}	$P_{TR1} = T_{R1}\omega_{R1}$
	PwrR2	For the Shaft merge configuration, mechanical power from second input shaft	P_{TR2}	$P_{TR2} = T_{R2}\omega_{R2}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrDampLoss	Mechanical damping loss	$P_d = -\left(b_1 \dot{\theta}_1 ^2 + b_2 \dot{\theta}_2 ^2\right)$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	PwrStoredShft	Rate change in spring energy	$P_s = \left(k_1\theta_1\dot{\theta}_1 + k_2\theta_2\dot{\theta}_2\right)$

The equations use these variables.

T_R	Shaft R torque
T_C	Shaft C torque
ω_R	Shaft R angular velocity
ω_C	Shaft C angular velocity
θ	Coupled shaft rotation
k	Shaft torsional stiffness
b	Rotational viscous damping
P_t	Total mechanical power
P_d	Power loss due to damping
P_s	Rate change of stored spring energy

Ports

Input

RSpd — Input shaft speed

scalar

Input shaft rotational velocity, ω_{in} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

C1Spd — First output shaft speed

scalar

First output shaft rotational velocity, ω_{1out} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

C2Spd — Second output shaft speed

scalar

Second output shaft rotational velocity, ω_{2out} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

CSpd — Input speed

scalar

Output shaft rotational velocity, ω_{out} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

R1Spd — First input shaft speed

scalar

First input shaft rotational velocity, ω_{1in} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

R2Spd – Second input shaft speed

scalar

Second input shaft rotational velocity, ω_{2in} , in rad/s.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

R – Input shaft angular velocity and torque

two-way connector port

Input shaft angular velocity, ω_{in} , in rad/s and torque, T_{in} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft split

R1 – First input shaft angular velocity and torque

two-way connector port

First input shaft angular velocity, ω_{1in} , in rad/s and torque, T_{1in} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft merge

R2 – Second input shaft angular velocity and torque

two-way connector port

Second input shaft angular velocity, ω_{2in} , in rad/s and torque, T_{2in} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft merge

Output

Info – Bus signal

bus

If you set **Coupling Configuration** to Shaft split, the Info bus contains these signals.

Signal		Description	Variable	Units	
Trq	R	Input shaft torque	T_{in}	N·m	
	C1	First output shaft torque	T_{1out}	N·m	
	C2	Second output shaft torque	T_{2out}	N·m	
	Damp	C1	First output shaft damping torque	$b_1\omega_{1out}$	N·m
		C2	Second output shaft damping torque	$b_2\omega_{2out}$	N·m
	Spring	C1	First output shaft spring torque	$k_1\theta_1$	N·m
C2		Second output shaft spring torque	$k_2\theta_2$	N·m	
Spd	R	Input shaft angular velocity	ω_{in}	rad/s	
	C1	First output shaft angular velocity	ω_{1out}	rad/s	
	C2	Second output shaft angular velocity	ω_{2out}	rad/s	
	deltadot1	Difference in input and first output shaft angular velocity	$\dot{\theta}_1$	rad/s	
	deltadot2	Difference in input and second output shaft angular velocity	$\dot{\theta}_2$	rad/s	
PwrInfo	PwrTrnsfrd	PwrR	Mechanical power from input shaft	P_{TR}	W
		PwrC1	Mechanical power from first output shaft	P_{TC1}	W
		PwrC2	Mechanical power from second output shaft	P_{TC2}	W
	PwrNotTrnsfrd	PwrDampLoss	Mechanical damping loss	P_d	W
	PwrStored	PwrStoredShft	Rate change of stored internal torsional energy	P_s	W

If you set **Coupling Configuration** to Shaft merge, the Info bus contains these signals.

Signal		Description	Variable	Units
Trq	C	Output shaft torque	T_{out}	N·m
	R1	First input shaft torque	T_{1in}	N·m
	R2	Second input shaft torque	T_{2in}	N·m

Signal			Description	Variable	Units
	Damp	R1	First input shaft damping torque	$b_1\omega_{1in}$	N·m
		R2	Second in shaft damping torque	$b_2\omega_{2in}$	N·m
	Spring	R1	First input shaft spring torque	$k_1\theta_1$	N·m
		R2	Second in shaft spring torque	$k_2\theta_2$	N·m
Spd	C		Output shaft angular velocity	ω_{out}	rad/s
	R1		First input shaft angular velocity	ω_{1in}	rad/s
	R2		Second input shaft angular velocity	ω_{2in}	rad/s
	deltadot1		Difference in first input and output shaft angular velocity	$\dot{\theta}_1$	rad/s
	deltadot2		Difference in second input and output shaft angular velocity	$\dot{\theta}_2$	rad/s
PwrInfo	PwrTrnsfrd	PwrC	Mechanical power from output shaft	P_{TC}	W
		PwrR1	Mechanical power from first input shaft	P_{TR1}	W
		PwrR2	Mechanical power from second input shaft	P_{TR2}	W
	PwrNotTrnsfrd	PwrDampLoss	Mechanical damping loss	P_d	W
	PwrStored	PwrStoredShft	Rate change of stored internal torsional energy	P_s	W

Dependencies

To enable this port, select **Output Info bus**.

RTrq – Input shaft torque

scalar

Input shaft torque, T_{in} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

C1Trq – First output shaft torque

scalar

First output shaft torque, T_{1out} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

C2Trq — Second output shaft torque

scalar

Second output shaft torque, T_{2out} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft split

CTrq — Output shaft torque

scalar

Output shaft torque, T_{out} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

R1Trq — First input shaft torque

scalar

First input shaft torque, T_{1in} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

R2Trq — Second input shaft torque

scalar

Second input shaft torque, T_{2in} , in N·m.

Dependencies

To enable this port, set both of these parameters:

- **Port Configuration** to Simulink
- **Coupling Configuration** to Shaft merge

C1 — First output shaft angular velocity and torque

two-way connector port

First output shaft angular velocity, ω_{1out} , in rad/s and torque, T_{1out} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft split

C2 — Second output shaft angular velocity and torque

two-way connector port

Second output shaft angular velocity, ω_{2out} , in rad/s and torque, T_{2out} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft split

C — Output shaft angular velocity and torque

two-way connector port

Output shaft angular velocity, ω_{out} , in rad/s and torque, T_{out} , in N·m.

Dependencies

To enable this port, select:

- **Port Configuration**>Two-way connection
- **Coupling Configuration**>Shaft merge

Parameters**Block Options****Port Configuration — Specify configuration**

Simulink (default) | Two-way connection

Specify the port configuration.

Coupling Configuration — Specify configuration

Shaft split (default) | Shaft merge

Specify the coupling type.

Output Info bus — Selection

off (default) | on

Select to create the Info output port.

Coupling 1**Torsional stiffness, k1 — Stiffness**

5e4 (default) | scalar

Rotational inertia, k_1 , in N·m/rad.

Torsional damping, b1 — Damping

1e2 (default) | scalar

Torsional damping, b_1 , in N·m· s/rad.

Damping cutoff frequency, omega1_c — Frequency

3000 (default) | scalar

Damping cutoff frequency, in rad/s.

Coupling 2

Torsional stiffness, k2 — Stiffness

5e4 (default) | scalar

Rotational inertia, k_2 , in N·m/rad.

Torsional damping, b2 — Damping

1e2 (default) | scalar

Torsional damping, b_2 , in N·m· s/rad.

Damping cutoff frequency, omega2_c — Frequency

3000 (default) | scalar

Damping cutoff frequency, in rad/s.

Version History

Introduced in R2017b

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Rotational Inertia | Torsional Compliance

Torsional Compliance

Parallel spring-damper

Library: Powertrain Blockset / Drivetrain / Couplings
Vehicle Dynamics Blockset / Powertrain / Drivetrain / Couplings



Description

The Torsional Compliance block implements a parallel spring-damper to couple two rotating driveshafts. The block uses the driveshaft angular velocities, torsional stiffness, and torsional damping to determine the torques.

$$T_R = -(\omega_R - \omega_C)b - \theta k$$

$$T_C = (\omega_R - \omega_C)b + \theta k$$

$$\dot{\theta} = (\omega_R - \omega_C)$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal	Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrR	Mechanical power from driveshaft R	$P_{TR} = T_R \omega_R$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrC	Mechanical power from driveshaft C	$P_{TC} = T_C \omega_C$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrDampLoss	Mechanical damping loss	$P_d = -b \dot{\theta} ^2$
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 			

Bus Signal		Description	Variable	Equations	
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredShft	Rate change in spring energy	P_s	$P_s = -\theta k \dot{\theta}$

The equations use these variables.

T_R	Driveshaft R torque
T_C	Driveshaft C torque
ω_R	Driveshaft R angular velocity
ω_C	Driveshaft C angular velocity
θ	Coupled driveshaft rotation
k	Driveshaft torsional stiffness
b	Rotational viscous damping
P_d	Power loss due to damping
P_s	Rate change of stored spring energy

Ports

Input

RSpd — Driveshaft R angular velocity

scalar

Input driveshaft angular velocity, in rad/s.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

CSpd — Driveshaft C angular velocity

scalar

Output driveshaft angular velocity, in rad/s.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

R — Angular velocity and torque

two-way connector port

Angular velocity in rad/s. Torque is in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Two-way connection.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
Trq	R	Input driveshaft torque	T_R	N·m	
	C	Output driveshaft torque	T_C	N·m	
	Damp	Damping torque	$T_s = b\dot{\theta}$	N·m	
	Spring	Spring torque	$T_d = k\theta$	N·m	
Spd	R	Input driveshaft angular velocity	ω_R	rad/s	
	C	Output driveshaft angular velocity	ω_C	rad/s	
	deltadot	Difference in input and output driveshaft angular velocity	$\dot{\theta}$	rad/s	
PwrInfo	PwrTrnsfrd	PwrR	Mechanical power from driveshaft R	P_{TR}	W
		PwrC	Mechanical power from driveshaft C	P_{TC}	W
	PwrNotTrnsfrd	PwrDampLoss	Power loss due to damping	P_d	W
	PwrStored	PwrStoredShft	Rate change of stored internal kinetic energy	P_s	W

Dependencies

To enable this port, select **Output Info bus**.

RTrq — Driveshaft R torque

scalar

Input drive shaft torque, in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

CTrq — Driveshaft C torque

scalar

Applied output driveshaft torque, in N·m.

Dependencies

To enable this port, for **Port Configuration**, select Simulink.

C – Angular velocity and torque

two-way connector port

Angular velocity in rad/s. Torque is in N·m.

Dependencies

To enable this port, for **Port Configuration**, select `Two-way connection`.

Parameters

Block Options

Port Configuration – Specify configuration

Simulink (default) | `Two-way connection`

Specify the port configuration.

Dependencies

Specifying Simulink creates these ports:

- RSpd
- CSpd
- RTrq
- CTrq

Specifying `Two-way connection` creates these ports:

- R
- C

Output Info bus – Selection

off (default) | on

Select to create the Info output port.

Torsional stiffness, k – Inertia

1e4 (default) | scalar

Torsional stiffness, in N·m/rad.

Torsional damping, b – Damping

1e2 (default) | scalar

Torsional damping, in N·m·s/rad.

Initial deflection, theta_o – Angular

0 (default) | scalar

Initial deflection, in rad.

Initial velocity difference, domega_o – Angular

0 (default) | scalar

Initial velocity difference, in rad/s.

Damping cut-off frequency, omega_c — Frequency

3000 (default) | scalar

Damping cut-off frequency, in rad/s.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

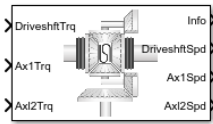
See Also

Rotational Inertia | Split Torsional Compliance

Limited Slip Differential

Limited differential as a planetary bevel gear

Library: Powertrain Blockset / Drivetrain / Final Drive Unit
Vehicle Dynamics Blockset / Powertrain / Drivetrain / Final Drive Unit



Description

The Limited Slip Differential block implements a differential as a planetary bevel gear train. The block matches the driveshaft bevel gear to the crown (ring) bevel gear. You can specify:

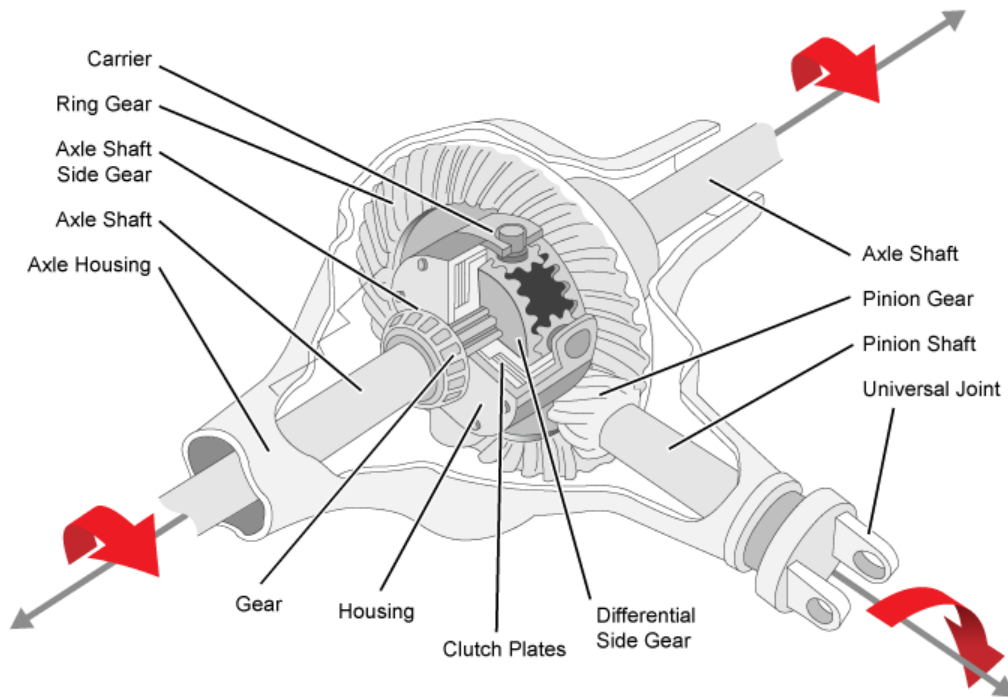
- Carrier-to-driveshaft ratio
- Crown wheel location
- Viscous and damping coefficients for the axles and carrier
- Type of slip coupling

Use the block in system-level driveline analysis to account for the power transfer from the transmission to the wheels. The block is suitable for use in hardware-in-the-loop (HIL) and optimization workflows. All the parameters are tunable.

In a limited slip differential, to prevent one of the wheels from slipping, the differential splits the torque applied to the left and right axles. With different torque applied to the axles, the wheels can move at different angular velocities, preventing slip. The block implements three methods for coupling the different torques applied to the axes:

- Pre-loaded ideal clutch
- Slip speed-dependent torque data
- Input torque dependent torque data

The block uses a coordinate system that produces positive tire and vehicle motion for standard engine, transmission, and differential configurations. The arrows indicate positive motion.



Efficiency

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrDriveshft	Mechanical power from driveshaft $\eta T_d \omega_d$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrAxl1	Mechanical power from axle 1 $\eta T_1 \omega_1$
		PwrAxl2	Mechanical power from axle 2 $\eta T_2 \omega_2$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMechLoss	Total power loss $\dot{W}_{loss} = -(P_t + P_d + P_c) + P_s$ $P_t = \eta(T_d \omega_d + T_1 \omega_1 + T_2 \omega_2)$
		PwrDampLoss	Power loss due to damping $P_d = -(b_1 \omega_1 + b_2 \omega_2 + b_d \omega_d)$
		PwrCplngLoss	Power loss due to clutch $P_c = T_c \bar{\omega} $
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredShft	Rate change of stored internal energy $P_s = -(\omega_1 \dot{\omega}_1 J_1 + \omega_2 \dot{\omega}_2 J_2 + \omega_d \dot{\omega}_d J_d)$	

Dynamics

The Limited Slip Differential block implements these differential equations to represent the mechanical dynamic response for the crown gear, left axle, and right axle.

Mechanical Dynamic Response	Differential Equation
Crown Gear	$\dot{\omega}_d J_d = \eta T_d - \omega_d b_d - T_i$
Left Axle	$\dot{\omega}_1 J_1 = \eta T_1 - \omega_1 b_1 - T_{i1}$
Right Axle	$\dot{\omega}_2 J_2 = \eta T_2 - \omega_2 b_2 - T_{i2}$

The block assumes rigid coupling between the crown gear and axles. These constraint equations apply.

$$\eta T_1 = \frac{N}{2} T_i - \frac{1}{2} T_c$$

$$\eta T_2 = \frac{N}{2} T_i + \frac{1}{2} T_c$$

$$\omega_d = \frac{N}{2}(\omega_1 + \omega_2)$$

The equations use these variables.

N	Carrier-to-driveshaft gear ratio
J_d	Rotational inertia of the crown gear assembly
b_d	Crown gear linear viscous damping
ω_d	Driveshaft angular speed
ϖ	Slip speed
J_1	Axle 1 rotational inertia
b_1	Axle 1 linear viscous damping
ω_1	Axle 1 speed
J_2	Axle 2 rotational inertia
b_2	Axle 2 linear viscous damping
ω_2	Axle 2 angular speed
η	Efficiency
T_d	Driveshaft torque
T_1	Axle 1 torque
T_2	Axle 2 torque
T_i	Axle internal resistance torque
T_{i1}	Axle 1 internal resistance torque
T_{i2}	Axle 2 internal resistance torque
μ	Coefficient of friction
R_{eff}	Effective clutch radius
R_o	Annular disk outer radius
R_i	Annular disk inner radius
F_c	Clutch force
T_c	Clutch torque
μ	Coefficient of friction

Table blocks in the Limited Slip Differential have these parameter settings:

- **Interpolation method** – Linear
- **Extrapolation method** – Clip

Ideal Clutch Coupling

The ideal clutch coupling model uses the axle slip speed and friction to calculate the clutch torque. The friction coefficient is a function of the slip speed.

$$T_c = F_c N \mu(|\varpi|) R_{eff} \tanh(4|\varpi|)$$

The disc radii determine the effective clutch radius over which the clutch force acts.

$$R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$$

The angular velocities of the axles determine the slip speed.

$$\varpi = \omega_1 - \omega_2$$

Slip Speed Coupling

To calculate the clutch torque, the slip speed coupling model uses torque data that is a function of slip speed. The angular velocities of the axles determine the slip speed.

$$\varpi = \omega_1 - \omega_2$$

Input Torque Coupling

To calculate the clutch torque, the input torque coupling model uses torque data that is a function of input torque.

The Open Differential block assumes rigid coupling between the crown gear and axles. These constraint equations apply.

$$\eta T_{i1} = \eta T_{i2} = \frac{N}{2} T_i$$

$$\omega_d = \frac{N}{2} (\omega_1 + \omega_2)$$

Ports

Inputs

DriveshaftTrq — Torque

scalar

Applied input torque, typically from the engine crankshaft, in N·m.

Axl1Trq — Torque

scalar

Axle 1 torque, T_1 , in N·m.

Axl2Trq — Torque

scalar

Axle 2 torque, T_2 , in N·m.

Temp — Temperature

scalar

Temperature, in K.

Dependencies

To enable this port:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Select **Input temperature**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description		Units	
Driveshft	DriveshftTrq	Driveshaft torque	N·m	
	DriveshftSpd	Driveshaft speed	rad/s	
Axl1	Axl1Trq	Axle 1 torque	N·m	
	Axl1Spd	Axle 1 speed	rad/s	
Axl2	Axl2Trq	Axle 2 torque	N·m	
	Axl2Spd	Axle 2 speed	rad/s	
Cplng	CplngTrq	Torque coupling	N·m	
	CplngSlipSpd	Slip speed	rad/s	
PwrInfo	PwrTrnsfrd	PwrDriveshft	Mechanical power from driveshaft	W
		PwrAxl1	Mechanical power from axle 1	W
		PwrAxl2	Mechanical power from axle 2	W
	PwrNotTrnsfrd	PwrMechLoss	Total power loss	W
		PwrDampLoss	Power loss due to damping	W
		PwrCplngLoss	Power loss due to clutch	W
	PwrStoredShft	PwrStoredShft	Rate change of stored internal energy	W

DriveshftSpd – Angular speed

scalar

Driveshaft angular speed, ω_d , in rad/s.

Axl1Spd – Angular speed

scalar

Axle 1 angular speed, ω_1 , in rad/s.

Axl2Spd – Angular speed

scalar

Axle 2 angular speed, ω_2 , in rad/s.

Parameters

Block Options

Efficiency factors — Specify configuration

Constant (default) | Driveshaft torque, speed and temperature

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Interpolation method — Method

Flat | Nearest | Linear point-slope | Linear Lagrange | Cubic spline

For more information, see “Interpolation Methods”.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Input temperature — Create input port

off (default) | on

Select to create input port Temp for the temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Open Differential

Crown wheel (ring gear) located — Specify crown wheel connection

To the left of center-line (default) | To the right of center-line

Specify the crown wheel connection to the driveshaft.

Carrier to drive shaft ratio, NC/ND – Ratio

4 (default) | scalar

Carrier-to-driveshaft gear ratio, N .

Carrier inertia, Jd – Inertia

.1 (default) | scalar

Rotational inertia of the crown gear assembly, J_d , in $\text{kg}\cdot\text{m}^2$. You can include the driveshaft inertia.

Carrier damping, bd – Damping

1e-3 (default) | scalar

Crown gear linear viscous damping, b_d , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 1 inertia, Jw1 – Inertia

.1 (default) | scalar

Axle 1 rotational inertia, J_1 , in $\text{kg}\cdot\text{m}^2$.

Axle 1 damping, bw1 – Damping

1e-3 (default) | scalar

Axle 1 linear viscous damping, b_1 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 2 inertia, Jw2 – Inertia

.1 (default) | scalar

Axle 2 rotational inertia, J_2 , in $\text{kg}\cdot\text{m}^2$.

Axle 2 damping, bw2 – Damping

1e-3 (default) | scalar

Axle 2 linear viscous damping, b_2 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 1 initial velocity, omegaw1o – Angular velocity

0 (default) | scalar

Axle 1 initial velocity, ω_{o1} , in rad/s.

Axle 2 initial velocity, omegaw2o – Angular velocity

0 (default) | scalar

Axle 2 initial velocity, ω_{o2} , in rad/s.

Constant efficiency factor, eta – Efficiency

1 (default) | scalar

Constant efficiency, η .

Dependencies

To enable this parameter, set **Efficiency factors** to Constant.

Efficiency lookup table, eta_tbl — Lookup table

M-by-N-by-L array

Dimensionless array of values for efficiency as a function of:

- M input torques
- N input speed
- L air temperatures

Each value specifies the efficiency for a specific combination of torque, speed, and temperature. The array size must match the dimensions defined by the torque, speed, and temperature breakpoint vectors.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency torque breakpoints, Trq_bpts — Torque breakpoints

[25, 50, 75, 100, 150, 200, 250] (default) | 1-by-M vector

Vector of input torque, breakpoints for efficiency, in N·m.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency speed breakpoints, omega_bpts — Speed breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | 1-by-N vector

Vector of speed, breakpoints for efficiency, in rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency temperature breakpoints, Temp_bpts — Temperature breakpoints

[290 358] (default) | 1-by-L vector

Vector of ambient temperature breakpoints for efficiency, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Ambient temperature, Tamb — Ambient temperature

297.15 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Clear **Input temperature**.

Slip Coupling

Coupling type – Torque coupling

Pre-loaded ideal clutch (default) | Slip speed dependent torque data | Input torque dependent torque data

Specify the type of torque coupling.

Number of disks, Ndisks – Torque coupling

4 (default) | scalar

Number of disks.

Dependencies

To enable the ideal clutch parameters, select Pre-loaded ideal clutch for the **Coupling type** parameter.

Effective radius, Reff – Radius

.20 (default) | scalar

The effective radius, R_{eff} , used with the applied clutch friction force to determine the friction force. The effective radius is defined as:

$$R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$$

The equation uses these variables.

R_o Annular disk outer radius

R_i Annular disk inner radius

Dependencies

To enable the clutch parameters, select Pre-loaded ideal clutch for the **Coupling type** parameter.

Nominal preload force, Fc – Force

500 (default) | scalar

Nominal preload force, in N.

Dependencies

To enable the clutch parameters, select Pre-loaded ideal clutch for the **Coupling type** parameter.

Friction coefficient vector, muc – Friction

[.16 0.13 0.115 0.11 0.105 0.1025 0.10125] (default) | vector

Friction coefficient vector.

Dependencies

To enable the clutch parameters, select Pre-loaded ideal clutch for the **Coupling type** parameter.

Slip speed vector, $d\omega$ – Angular velocity

[0 10 20 40 60 80 100] (default) | vector

Slip speed vector, in rad/s.

Dependencies

To enable the clutch parameters, select Pre-loaded ideal clutch for the **Coupling type** parameter.

Torque - slip speed vector, T_{dw} – Torque

[-100, -90, -50, -5, 0, 5, 50, 90, 100] (default) | vector

Torque vector, in N·m.

Dependencies

To enable the slip speed parameters, select Slip speed dependent torque data for the **Coupling type** parameter.

Slip speed vector, $d\omega_T$ – Angular velocity

[-200, -175, -100, -50, 0, 50, 100, 175, 200] (default) | vector

Slip speed vector, in rad/s.

Dependencies

To enable the slip speed parameters, select Slip speed dependent torque data for the **Coupling type** parameter.

Torque - input torque vector, T_{Tin} – Torque

[-200 -175 -100 -50 0 50 100 175 200] (default) | vector

Torque vector, in N·m.

Dependencies

To enable the input torque parameters, select Input torque dependent torque data for the **Coupling type** parameter.

Input torque vector, T_{in} – Torque

[-200 -175 -100 -50 0 50 100 175 200] (default) | vector

Torque vector, in N·m.

Dependencies

To enable the input torque parameters, select Input torque dependent torque data for the **Coupling type** parameter.

Coupling time constant, τ_C – Constant

.01 (default) | scalar

Coupling time constant, in s.

Version History

Introduced in R2017a

References

- [1] Deur, J., Ivanović, V., Hancock, M., and Assadian, F. "Modeling of Active Differential Dynamics." In ASME proceedings. *Transportation Systems*. Vol. 17, pp: 427-436.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

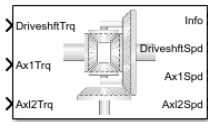
See Also

Open Differential

Open Differential

Differential as a planetary bevel gear

Library: Powertrain Blockset / Drivetrain / Final Drive Unit
Vehicle Dynamics Blockset / Powertrain / Drivetrain / Final Drive Unit



Description

The Open Differential block implements a differential as a planetary bevel gear train. The block matches the driveshaft bevel gear to the crown (ring) bevel gear. You can specify:

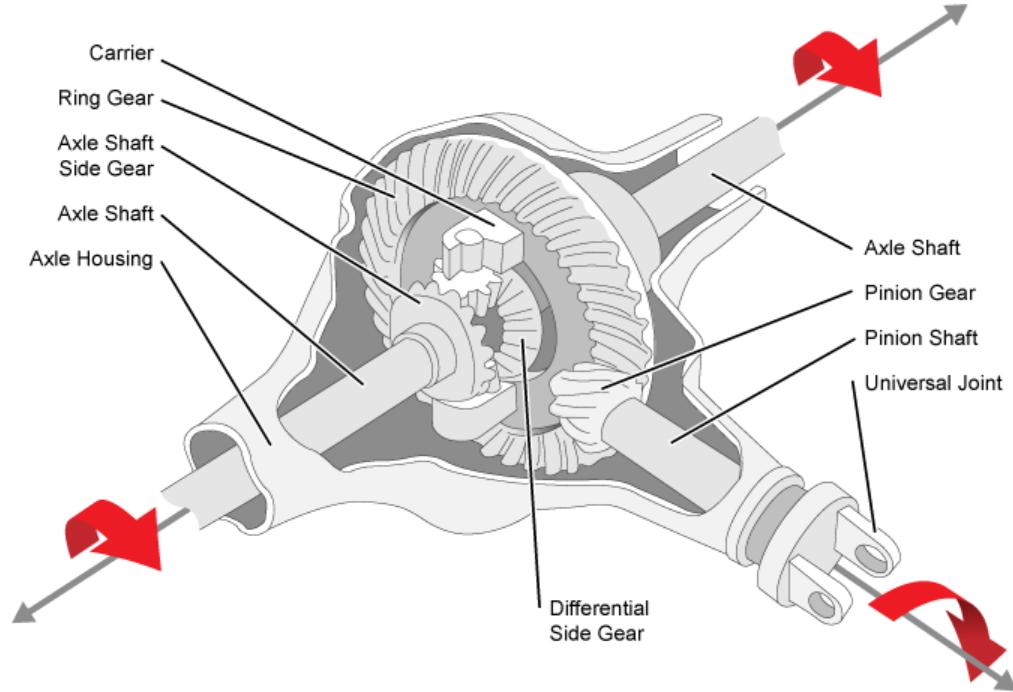
- Carrier-to-driveshaft ratio
- Crown wheel location
- Viscous and damping coefficients for the axles and carrier

Use the Open Differential block to:

- Dynamically couple the post-transmission driveshaft to the wheel axles or universal joints
- Model simplified or older drivetrains when optimal traction control does not require passive or active torque vectoring
- Model mechanical power splitting in generic gearbox and drive line scenarios

The block is suitable for use in hardware-in-the-loop (HIL) and optimization workflows. All the parameters are tunable.

The block uses a coordinate system that produces positive tire and vehicle motion for standard engine, transmission, and differential configurations. The arrows indicate positive motion.



Efficiency

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrDriveshft	Mechanical power from driveshaft $\eta T_d \omega_d$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrAxl1	Mechanical power from axle 1 $\eta T_1 \omega_1$
		PwrAxl2	Mechanical power from axle 2 $\eta T_2 \omega_2$
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMechLoss	Total power loss $\dot{W}_{loss} = -(P_t + P_d) + P_s$
		PwrDampLoss	Power loss due to damping $P_d = -(b_1 \omega_1 + b_2 \omega_2 + b_d \omega_d)$
PwrStored — Stored energy rate of change	<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredShft	Rate change of stored internal energy $P_s = -(\omega_1 \dot{\omega}_1 J_1 + \omega_2 \dot{\omega}_2 J_2 + \omega_d \dot{\omega}_d J_d)$

Dynamics

The Open Differential block implements these differential equations to represent the mechanical dynamic response for the crown gear, left axle, and right axle.

Mechanical Dynamic Response	Differential Equation
Crown Gear	$\dot{\omega}_d J_d = \eta T_d - \omega_d b_d - T_i$
Left Axle	$\dot{\omega}_1 J_1 = \eta T_1 - \omega_1 b_1 - T_{i1}$
Right Axle	$\dot{\omega}_2 J_2 = \eta T_2 - \omega_2 b_2 - T_{i2}$

The Open Differential block assumes rigid coupling between the crown gear and axles. These constraint equations apply.

$$\eta T_{i1} = \eta T_{i2} = \frac{N}{2} T_i$$

$$\omega_d = \frac{N}{2} (\omega_1 + \omega_2)$$

The equations use these variables.

N	Carrier-to-driveshaft gear ratio
J_d	Rotational inertia of the crown gear assembly
b_d	Crown gear linear viscous damping
ω_d	Driveshaft angular speed
η	Differential efficiency
J_1	Axle 1 rotational inertia
b_1	Axle 1 linear viscous damping
ω_1	Axle 1 speed
J_2	Axle 2 rotational inertia
b_2	Axle 2 linear viscous damping
ω_2	Axle 2 angular speed
T_d	Driveshaft torque
T_1	Axle 1 torque
T_2	Axle 2 torque
T_i	Driveshaft internal resistance torque
T_{i1}	Axle 1 internal resistance torque
T_{i2}	Axle 2 internal resistance torque

Ports

Inputs

DriveshaftTrq — Torque

scalar

Applied input torque, typically from the engine crankshaft, in N·m.

Ax11Trq — Torque

scalar

Axle 1 torque, T_1 , in N·m.

Ax12Trq — Torque

scalar

Axle 2 torque, T_2 , in N·m.

Temp — Temperature

scalar

Temperature, in K.

Dependencies

To enable this port:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Select **Input temperature**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
Driveshft	DriveshftTrq	Driveshaft torque	N·m	
	DriveshftSpd	Driveshaft speed	rad/s	
Axl1	Axl1Trq	Axle 1 torque	N·m	
	Axl1Spd	Axle 1 speed	rad/s	
Axl2	Axl2Trq	Axle 2 torque	N·m	
	Axl2Spd	Axle 2 speed	rad/s	
PwrInfo	PwrTrnsfrd	PwrDriveshft	Mechanical power from driveshaft	W
		PwrAxl1	Mechanical power from axle 1	W
		PwrAxl2	Mechanical power from axle 2	W
	PwrTrnsfrd	PwrMechLoss	Total power loss	W
		PwrDampLoss	Power loss due to damping	W
	PwrStored	PwrStoredShft	Rate change of stored internal energy	W

DriveshftSpd – Angular speed

scalar

Driveshaft angular speed, ω_d , in rad/s.

Axl1Spd – Angular speed

scalar

Axle 1 angular speed, ω_1 , in rad/s.

Axl2Spd – Angular speed

scalar

Axle 2 angular speed, ω_2 , in rad/s.

Parameters

Block Options

Efficiency factors — Specify configuration

Constant (default) | Driveshaft torque, speed and temperature

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Interpolation method — Method

Flat | Nearest | Linear point-slope | Linear Lagrange | Cubic spline

For more information, see “Interpolation Methods”.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Input temperature — Create input port

off (default) | on

Select to create input port Temp for the temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Crown wheel (ring gear) located — Specify crown wheel connection

To the left of center-line (default) | To the right of center-line

Specify the crown wheel connection to the driveshaft.

Carrier to drive shaft ratio, Ndiff – Ratio

4 (default) | scalar

Carrier-to-driveshaft gear ratio, N , dimensionless.**Carrier inertia, Jd – Inertia**

.1 (default) | scalar

Rotational inertia of the crown gear assembly, J_d , in $\text{kg}\cdot\text{m}^2$. You can include the driveshaft inertia.**Carrier damping, bd – Damping**

1e-3 (default) | scalar

Crown gear linear viscous damping, b_d , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.**Axle 1 inertia, Jw1 – Inertia**

.1 (default) | scalar

Axle 1 rotational inertia, J_1 , in $\text{kg}\cdot\text{m}^2$.**Axle 1 damping, bw1 – Damping**

1e-3 (default) | scalar

Axle 1 linear viscous damping, b_1 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.**Axle 2 inertia, Jw2 – Inertia**

.1 (default) | scalar

Axle 2 rotational inertia, J_2 , in $\text{kg}\cdot\text{m}^2$.**Axle 2 damping, bw2 – Damping**

1e-3 (default) | scalar

Axle 2 linear viscous damping, b_2 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.**Axle 1 initial velocity, omegaw1o – Angular velocity**

0 (default) | scalar

Axle 1 initial velocity, ω_{o1} , in rad/s .**Axle 2 initial velocity, omegaw2o – Angular velocity**

0 (default) | scalar

Axle 2 initial velocity, ω_{o2} , in rad/s .**Efficiency****Constant efficiency factor, eta – Efficiency**

1 (default) | scalar

Constant efficiency, η .**Dependencies**To enable this parameter, set **Efficiency factors** to Constant.

Efficiency lookup table, eta_tbl — Lookup table

M-by-N-by-L array

Dimensionless array of values for efficiency as a function of:

- M input torques
- N input speed
- L air temperatures

Each value specifies the efficiency for a specific combination of torque, speed, and temperature. The array size must match the dimensions defined by the torque, speed, and temperature breakpoint vectors.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency torque breakpoints, Trq_bpts — Torque breakpoints

[25, 50, 75, 100, 150, 200, 250] (default) | 1-by-M vector

Vector of input torque, breakpoints for efficiency, in N·m.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency speed breakpoints, omega_bpts — Speed breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | 1-by-N vector

Vector of speed, breakpoints for efficiency, in rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency temperature breakpoints, Temp_bpts — Temperature breakpoints

[290 358] (default) | 1-by-L vector

Vector of ambient temperature breakpoints for efficiency, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Ambient temperature, Tamb — Ambient temperature

297.15 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Clear **Input temperature**.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

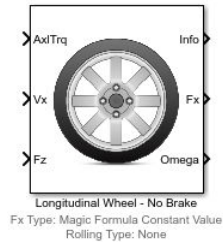
See Also

Limited Slip Differential

Longitudinal Wheel

Longitudinal wheel with disc, drum, or mapped brake

Library: Powertrain Blockset / Drivetrain / Wheels
 Vehicle Dynamics Blockset / Wheels and Tires



Description

The Longitudinal Wheel block implements the longitudinal behavior of an ideal wheel. You can specify the longitudinal force and rolling resistance calculation method, and brake type. Use the block in driveline and longitudinal vehicle simulations where low frequency tire-road and braking forces are required to determine vehicle acceleration, braking, and wheel-rolling resistance. For example, you can use the block to determine the torque and power requirements for a specified drive cycle or braking event. The block is not suitable for applications that require combined lateral slip.

There are four types of Longitudinal Wheel blocks. Each block implements a different brake type.

Block Name	Brake Type Setting	Brake Implementation
Longitudinal Wheel - No Brake	None	None
Longitudinal Wheel - Disc Brake	Disc	Brake that converts the brake cylinder pressure into a braking force.
Longitudinal Wheel - Drum Brake	Drum	Simplex drum brake that converts the applied force and brake geometry into a net braking torque.
Longitudinal Wheel - Mapped Brake	Mapped	Lookup table that is a function of the wheel speed and applied brake pressure.

The block models longitudinal force as a function of wheel slip relative to the road surface. To calculate the longitudinal force, specify one of these **Longitudinal Force** parameters.

Setting	Block Implementation
Magic Formula constant value	Magic Formula with constant coefficient for stiffness, shape, peak, and curvature.
Magic Formula pure longitudinal slip	Magic Formula with load-dependent coefficients that implement equations 4.E9 through 4.E18 in <i>Tire and Vehicle Dynamics</i> .
Mapped force	Lookup table that is a function of the normal force and wheel slip ratio.

To calculate the rolling resistance torque, specify one of these **Rolling Resistance** parameters.

Setting	Block Implementation
None	None
Pressure and velocity	Method in <i>Stepwise Coastdown Methodology for Measuring Tire Rolling Resistance</i> . The rolling resistance is a function of tire pressure, normal force, and velocity.
ISO 28580	Method specified in ISO 28580:2018, <i>Passenger car, truck and bus tyre rolling resistance measurement method – Single point test and correlation of measurement results</i> .
Magic Formula	Magic formula equations from 4.E70 in <i>Tire and Vehicle Dynamics</i> . The magic formula is an empirical equation based on fitting coefficients.
Mapped torque	Lookup table that is a function of the normal force and spin axis longitudinal velocity.

To calculate vertical motion, specify one of these **Vertical Motion** parameters.

Setting	Block Implementation
None	Block passes the applied chassis forces directly through to the rolling resistance and longitudinal force calculations.
Mapped stiffness and damping	Vertical motion depends on wheel stiffness and damping. Stiffness is a function of tire sidewall displacement and pressure. Damping is a function of tire sidewall velocity and pressure.

Rotational Wheel Dynamics

The block calculates the inertial response of the wheel subject to:

- Axle losses
- Brake and drive torque
- Tire rolling resistance
- Ground contact through the tire-road interface

The input torque is the summation of the applied axle torque, braking torque, and moment arising from the combined tire torque.

$$T_i = T_a - T_b + T_d$$

For the moment arising from the combined tire torque, the block implements tractive wheel forces and rolling resistance with first order dynamics. The rolling resistance has a time constant parameterized in terms of a relaxation length.

$$T_d(s) = \frac{1}{\frac{L_e}{|\omega| R_e} s + 1}$$

To calculate the rolling resistance torque, you can specify one of these **Rolling Resistance** parameters.

Setting	Block Implementation
None	Block sets rolling resistance, M_y , to zero.
Pressure and velocity	Block uses the method in SAE <i>Stepwise Coastdown Methodology for Measuring Tire Rolling Resistance</i> . The rolling resistance is a function of tire pressure, normal force, and velocity. Specifically, $M_y = R_e \{ a + b V_x + cV_x^2 \} \{ F_z \beta p_i a \} \tanh(4V_x)$
ISO 28580	Block uses the method specified in ISO 28580:2018, <i>Passenger car, truck and bus tyre rolling resistance measurement method – Single point test and correlation of measurement results</i> . The method accounts for normal load, parasitic loss, and thermal corrections from test conditions. Specifically, $M_y = R_e \left(\frac{F_z C_r}{1 + K_t(T_{amb} - T_{meas})} - F_{pl} \right) \tanh(\omega)$
Magic Formula	Block calculates the rolling resistance, M_y , using the Magic Formula equations from 4.E70 in <i>Tire and Vehicle Dynamics</i> . The magic formula is an empirical equation based on fitting coefficients.
Mapped torque	For the rolling resistance, M_y , the block uses a lookup table that is a function of the normal force and spin axis longitudinal velocity.

If the brakes are enabled, the block determines the braking locked or unlocked condition based on an idealized dry clutch friction model. Based on the lock-up condition, the block implements these friction and dynamic models.

If	Lock-Up Condition	Friction Model	Dynamic Model
$\omega \neq 0$ or $T_S < T_i + T_f - \omega b $	Unlocked	$T_f = T_k$ where, $T_k = F_c R_{eff} \mu_k \tanh[4(-\omega_d)]$ $T_s = F_c R_{eff} \mu_s$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$	$\dot{\omega} J = -\omega b + T_i + T_o$
$\omega = 0$ and $T_S \geq T_i + T_f - \omega b $	Locked	$T_f = T_s$	$\omega = 0$

The equations use these variables.

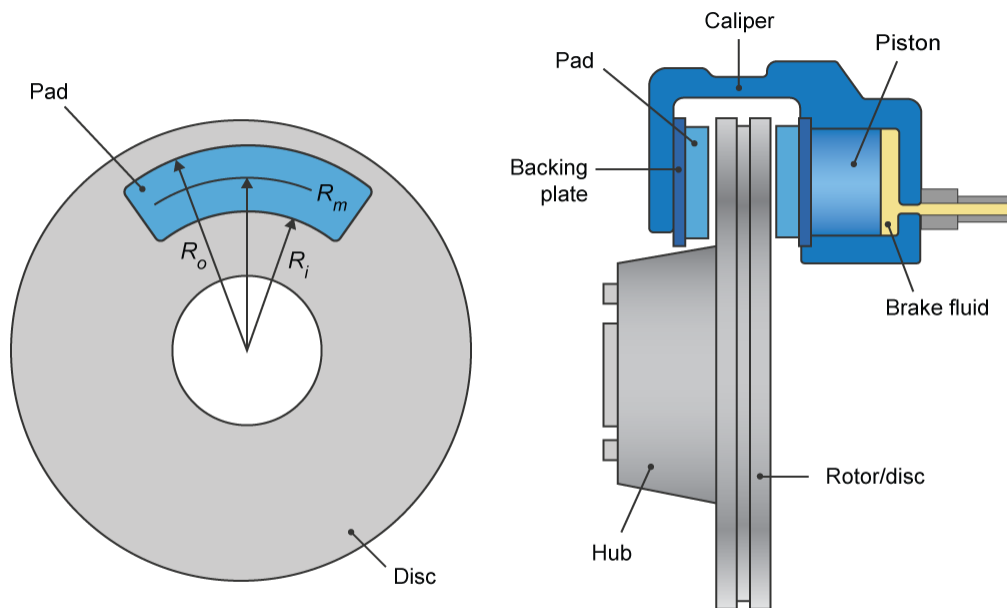
- ω Wheel angular velocity
- a Velocity-independent force component
- b Linear velocity force component
- c Quadratic velocity force component
- L_e Tire relaxation length
- J Moment of inertia

M_y	Rolling resistance torque
T_a	Applied axle torque
T_b	Braking torque
T_d	Combined tire torque
T_f	Frictional torque
T_i	Net input torque
T_k	Kinetic frictional torque
T_o	Net output torque
T_s	Static frictional torque
F_c	Applied clutch force
F_x	Longitudinal force developed by the tire road interface due to slip
R_{eff}	Effective clutch radius
R_o	Annular disk outer radius
R_i	Annular disk inner radius
R_e	Effective tire radius while under load and for a given pressure
V_x	Longitudinal axle velocity
F_z	Vehicle normal force
C_r	Rolling resistance constant
T_{amb}	Ambient temperature
T_{meas}	Measured temperature for rolling resistance constant
F_{pl}	Parasitic force loss
K_t	Thermal correction factor
α	Tire pressure exponent
β	Normal force exponent
p_i	Tire pressure
μ_s	Coefficient of static friction
μ_k	Coefficient of kinetic friction

Brakes

Disc

If you specify the **Brake Type** parameter `Disc`, the block implements a disc brake. This figure shows the side and front views of a disc brake.



A disc brake converts brake cylinder pressure from the brake cylinder into force. The disc brake applies the force at the brake pad mean radius.

The block uses these equations to calculate brake torque for the disc brake.

$$T = \begin{cases} \frac{\mu P \pi B_a^2 R_m N_{pads}}{4} & \text{when } N \neq 0 \\ \frac{\mu_{static} P \pi B_a^2 R_m N_{pads}}{4} & \text{when } N = 0 \end{cases}$$

$$R_m = \frac{R_o + R_i}{2}$$

The equations use these variables.

T	Brake torque
P	Applied brake pressure
N	Wheel speed
N_{pads}	Number of brake pads in disc brake assembly
μ_{static}	Disc pad-rotor coefficient of static friction
μ	Disc pad-rotor coefficient of kinetic friction
B_a	Brake actuator bore diameter
R_m	Mean radius of brake pad force application on brake rotor
R_o	Outer radius of brake pad

R_i Inner radius of brake pad

Drum

If you specify the **Brake Type** parameter Drum, the block implements a static (steady-state) simplex drum brake. A simplex drum brake consists of a single two-sided hydraulic actuator and two brake shoes. The brake shoes do not share a common hinge pin.

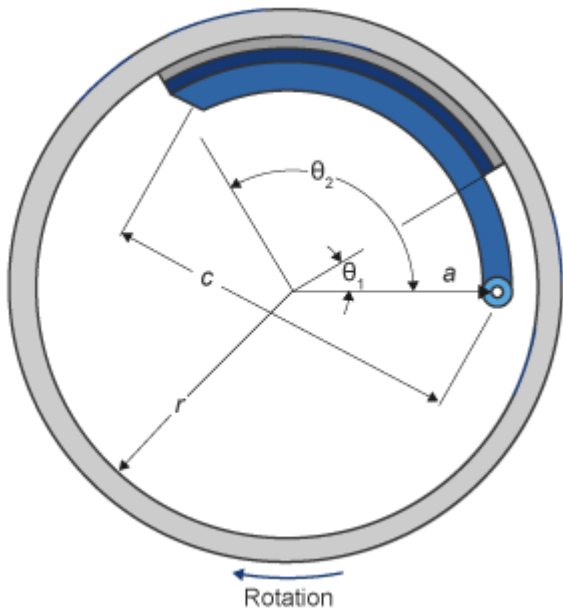
The simplex drum brake model uses the applied force and brake geometry to calculate a net torque for each brake shoe. The drum model assumes that the actuators and shoe geometry are symmetrical for both sides, allowing a single set of geometry and friction parameters to be used for both shoes.

The block implements equations that are derived from these equations in *Fundamentals of Machine Elements*.

$$T_{rshoe} = \left(\frac{\pi\mu cr(\cos\theta_2 - \cos\theta_1)B_a^2}{2\mu(2r(\cos\theta_2 - \cos\theta_1) + a(\cos^2\theta_2 - \cos^2\theta_1)) + ar(2\theta_1 - 2\theta_2 + \sin 2\theta_2 - \sin 2\theta_1)} \right) P$$

$$T_{lshoe} = \left(\frac{\pi\mu cr(\cos\theta_2 - \cos\theta_1)B_a^2}{-2\mu(2r(\cos\theta_2 - \cos\theta_1) + a(\cos^2\theta_2 - \cos^2\theta_1)) + ar(2\theta_1 - 2\theta_2 + \sin 2\theta_2 - \sin 2\theta_1)} \right) P$$

$$T = \begin{cases} T_{rshoe} + T_{lshoe} & \text{when } N \neq 0 \\ (T_{rshoe} + T_{lshoe}) \frac{\mu_{static}}{\mu} & \text{when } N = 0 \end{cases}$$



The equations use these variables.

- T Brake torque
- P Applied brake pressure
- N Wheel speed

μ_{static}	Disc pad-rotor coefficient of static friction
μ	Disc pad-rotor coefficient of kinetic friction
T_{rshoe}	Right shoe brake torque
T_{lshoe}	Left shoe brake torque
a	Distance from drum center to shoe hinge pin center
c	Distance from shoe hinge pin center to brake actuator connection on brake shoe
r	Drum internal radius
B_a	Brake actuator bore diameter
θ_1	Angle from shoe hinge pin center to start of brake pad material on shoe
θ_2	Angle from shoe hinge pin center to end of brake pad material on shoe

Mapped

If you specify the **Brake Type** parameter Mapped, the block uses a lookup table to determine the brake torque.

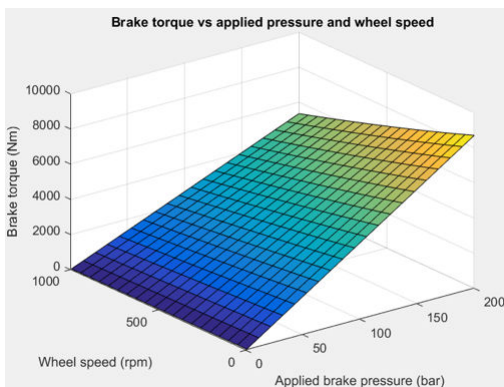
$$T = \begin{cases} f_{brake}(P, N) & \text{when } N \neq 0 \\ \left(\frac{\mu_{static}}{\mu}\right)f_{brake}(P, N) & \text{when } N = 0 \end{cases}$$

The equations use these variables.

T	Brake torque
$f_{brake}(P, N)$	Brake torque lookup table
P	Applied brake pressure
N	Wheel speed
μ_{static}	Friction coefficient of drum pad-face interface under static conditions
μ	Friction coefficient of disc pad-rotor interface

The lookup table for the brake torque, $f_{brake}(P, N)$, is a function of applied brake pressure and wheel speed, where:

- T is brake torque, in N·m.
- P is applied brake pressure, in bar.
- N is wheel speed, in rpm.



Longitudinal Force

To model the Longitudinal Wheel block longitudinal forces, you can use the Magic Formula. The model provides a steady-state *tire characteristic function* $F_x = f(\kappa, F_z)$, the longitudinal force F_x on the tire, based on:

- Vertical load F_z
- Wheel slip κ



The Magic Formula model uses these variables.

Ω	Wheel angular velocity
r_w	Wheel radius
V_x	Wheel hub longitudinal velocity
$r_w\Omega$	Tire tread longitudinal velocity
$V_{sx} = r_w\Omega - V_x$	Wheel slip velocity
$\kappa = V_{sx}/ V_x $	Wheel slip
F_z, F_{z0}	Vertical load and nominal vertical load on tire
$F_x = f(\kappa, F_z)$	Longitudinal force exerted on the tire at the contact point. Also a characteristic function f of the tire.

Magic Formula Constant Value

If you set **Longitudinal Force** to **Magic Formula constant value**, the block implements the Magic Formula as a specific form of the tire characteristic function, characterized by four dimensionless coefficients (B, C, D, E), or stiffness, shape, peak, and curvature:

$$F_x = f(\kappa, F_z) = F_z D \sin\left(C \tan^{-1}\left[\left\{B\kappa - E\left[B\kappa - \tan^{-1}(B\kappa)\right]\right\}\right]\right)$$

The slope of f at $\kappa = 0$ is $BCD \cdot F_z$.

The coefficients are based on empirical tire data. These values are typical sets of constant Magic Formula coefficients for common road conditions.

Surface	B	C	D	E
Dry tarmac	10	1.9	1	0.97
Wet tarmac	12	2.3	0.82	1
Snow	5	2	0.3	1
Ice	4	2	0.1	1

Magic Formula Pure Longitudinal Slip

If you set **Longitudinal Force** to Magic Formula pure longitudinal slip, the block implements a more general Magic Formula using dimensionless coefficients that are functions of the tire load. The block implements the longitudinal force equations in Chapter 4 of *Tire and Vehicle Dynamics*, including 4.E9 through 4.E18:

$$F_{x0} = D_x \sin \left(C_x \tan^{-1} \left[\left\{ B_x K_x - E_x [B_x K_x - \tan^{-1}(B_x K_x)] \right\} \right] \right) + S_{Vx}$$

where:

$$K_x = \kappa + S_{Hx}$$

$$C_x = p_{Cx1} \lambda_{Cx}$$

$$D_x = \mu_x F_z \zeta_1$$

$$\mu_x = (p_{Dx1} + p_{Dx2} df_z)(1 + p_{px3} dp_i + p_{px4} dp_i^2)(1 - p_{Dx3} v^2) \lambda_{\mu x}^*$$

$$E_x = (p_{Ex1} + p_{Ex2} df_z + p_{Ex3} df_z^2)[1 - p_{Ex4} \text{sgn}(\kappa_x)] \lambda_{Ex}$$

$$K_{xx} = F_z (p_{Kx1} + p_{Kx2} df_z) \exp(p_{Kx3} df_z)(1 + p_{px1} dp_i + p_{px2} dp_i^2)$$

$$B_x = K_{xx} / (C_x D_x + \varepsilon_x)$$

$$S_{Hx} = p_{Hx1} + p_{Hx2} df_z$$

$$S_{Vx} = F_z \cdot (p_{Vx1} + p_{Vx2} df_z) \lambda_{Vx} \lambda_{\mu x} \zeta_1$$

S_{Hx} and S_{Vx} represent offsets to the slip and longitudinal force in the force-slip function, or horizontal and vertical offsets if the function is plotted as a curve. μ_x is the longitudinal load-dependent friction coefficient. ε_x is a small number inserted to prevent division by zero as F_z approaches zero.

Vertical Dynamics

If you select no vertical degrees-of-freedom by setting **Vertical Motion** to None, the block passes the applied chassis forces directly through to the rolling resistance and longitudinal force calculations.

If you set **Vertical Motion** to Mapped stiffness and damping, the vertical motion depends on wheel stiffness and damping. Stiffness is a function of tire sidewall displacement and pressure. Damping is a function of tire sidewall velocity and pressure.

$$F_{ztire}(z, \dot{z}, P_{tire}) = F_{zk}(z, P_{tire}) + F_{zb}(\dot{z}, P_{tire})$$

The block determines the vertical response using this differential equation.

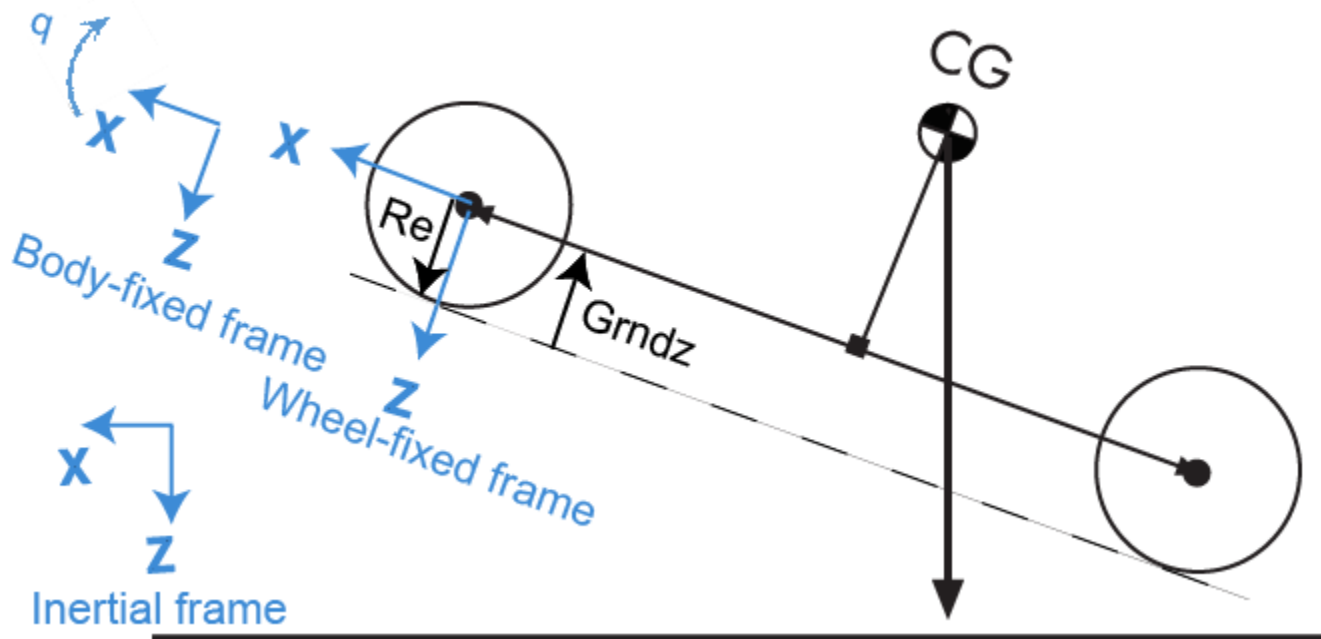
$$\ddot{z}m = F_{ztire} - F_z - mg$$

When you disable the vertical degree-of-freedom, the input normal force from the vehicle passes directly to the longitudinal and rolling force calculations.

$$\ddot{z} = \dot{z} = m = 0$$

$$F_{ztire} = mg$$

The block uses the wheel-fixed frame to resolve the vertical forces.



The equations use these variables.

F_{ztire}	Tire normal force along the wheel-fixed z-axis
m	Axle mass
F_{zk}	Tire normal force due to wheel stiffness along the wheel-fixed z-axis
F_{zb}	Tire normal force due to wheel damping along the wheel-fixed z-axis
F_z	Suspension or vehicle normal force along the wheel-fixed z-axis
P_{Tire}	Tire pressure
z, \dot{z}, \ddot{z}	Tire displacement, velocity, and acceleration, respectively, along the wheel-fixed z-axis

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrRoad	Tractive power applied from the axle $P_{road} = F_x V_x$
		PwrAxlTrq	External torque applied by the axle to the wheel $P_T = T\omega$

Bus Signal	Description	Equations
<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrFz	Vertical force applied to the wheel by the vehicle or suspension $P_{Fz} = F_z \dot{z}$
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrSlip	Tractive power loss $P_K = F_x V_x + (-F_{cp} R_e + M_y) \omega$
	PwrMyRoll	Rolling resistance power $P_{My} = M_y \omega$
	PwrMyBrk	Braking power $P_{brk} = M_{brk} \omega$
	PwrMyb	Rolling viscous damping loss $P_b = -b \omega^2$
	PwrFzDamp	Vertical damping power $P_{Fzb} = F_{zb} \dot{z}$
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredzdot	Rate of change of vertical kinetic energy $P_z = m \dot{z}^2$
	PwrStoredq	Rate of change of rotational kinetic energy $P_\omega = I_{yy} \dot{\omega} \omega$
	PwrStoredFsFzSprng	Rate of change of stored sidewall potential energy $P_{Fzk} = F_{zk} \dot{x}$
	PwrStoredGrvty	Rate of change of gravitational potential energy $P_g = -mg \dot{z}$

The equations use these variables.

ω	Wheel angular velocity
b	Linear velocity force component
F_x	Longitudinal force developed by the tire road interface due to slip
F_{cp}	Tire slip force at contact patch
F_z	Vehicle normal force
F_{zb}	Tire normal force due to wheel damping
F_{zk}	Tire normal force due to wheel stiffness
I_{yy}	Wheel rotational inertia
M_{brk}	Braking moment
M_y	Rolling resistance torque
R_e	Effective tire radius while under load and for a given pressure
T	Axle torque applied on wheel
V_x	Longitudinal axle velocity

z, \dot{z}, \ddot{z}	Tire displacement, velocity, and acceleration, respectively
ω	Wheel angular velocity
\dot{z}	Vehicle vertical velocity along the vehicle-fixed z-axis

Ports

Input

BrkPrs — Brake pressure

scalar

Brake pressure, in Pa.

Dependencies

To enable this port, for the **Brake Type** parameter, specify one of these types:

- Disc
- Drum
- Mapped

AxLTrq — Axle torque

scalar

Axle torque, T_a , about wheel spin axis, in N·m.

Vx — Velocity

scalar

Axle longitudinal velocity along vehicle(body)-fixed x-axis, in m/s.

Fz — Normal force

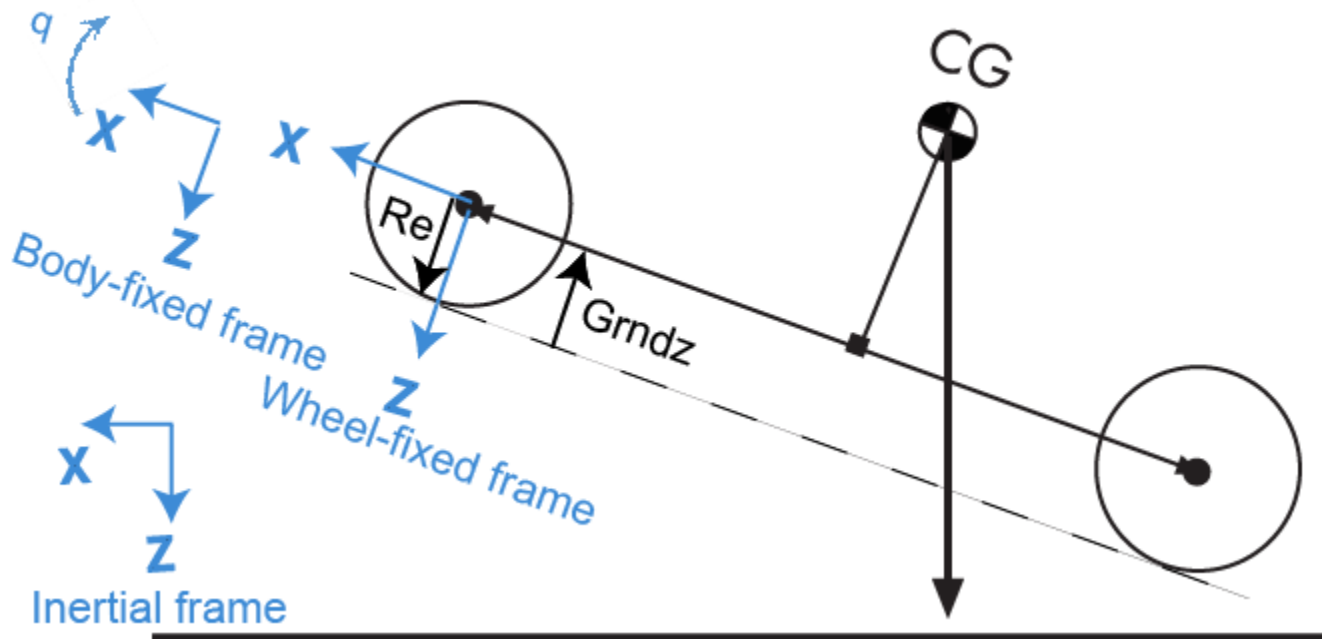
scalar

Absolute value of suspension or vehicle normal force along body-fixed z-axis, in N.

Gnd — Ground displacement

scalar

Ground displacement, $Grndz$, along negative wheel-fixed z-axis, in m.

**Dependencies**

To create Gnd:

- Set **Vertical Motion** to Mapped stiffness and damping.
- On the **Vertical** pane, select **Input ground displacement**.

lam_mux – Friction scaling factor

scalar

Longitudinal friction scaling factor, dimensionless.

Dependencies

To enable this port, select **Input friction scale factor**.

TirePrs – Tire pressure

scalar

Tire pressure, in Pa.

Dependencies

To enable this port:

- Set one of these parameters:
 - **Longitudinal Force** to Magic Formula pure longitudinal slip.
 - **Rolling Resistance** to Pressure and velocity or Magic Formula.
 - **Vertical Motion** to Mapped stiffness and damping.

- On the **Wheel Dynamics** pane, select **Input tire pressure**.

Tamb – Ambient temperature

scalar

Ambient temperature, T_{amb} , in K.

The ambient temperature, T_{amb} , is the temperature near tire in application environment, in K. For example, the measured ambient temperature is the ambient temperature near the tire when the vehicle is on the road.

Select to create input port Tamb to input the measured ambient temperature.

Dependencies

To enable this port:

- 1 Set **Rolling Resistance** to ISO 28580.
- 2 On the **Rolling Resistance** pane, select to **Input ambient temperature**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
AxlTrq	Axle torque about body-fixed y-axis	N·m
Omega	Wheel angular velocity about body-fixed y-axis	rad/s
Omegadot	Wheel angular acceleration about body-fixed y-axis	rad/s ²
Fx	Longitudinal vehicle force along body-fixed x-axis	N
Fz	Vertical vehicle force along body-fixed z-axis	N
Fzb	Tire normal force due to wheel damping along the wheel-fixed z-axis	N
Fzk	Tire normal force due to wheel stiffness along the wheel-fixed z-axis	N
My	Rolling resistance torque about body-fixed y-axis	N·m
Myb	Rolling resistance torque due to damping about body-fixed y-axis	N·m
Kappa	Slip ratio	NA

Signal		Description	Units	
Vx		Vehicle longitudinal velocity along body-fixed x-axis	m/s	
Re		Wheel effective radius along wheel-fixed z-axis	m	
BrkTrq		Brake torque about body-fixed y-axis	N·m	
BrkPrs		Brake pressure	Pa	
z		Wheel vertical deflection along wheel-fixed z-axis	m	
zdot		Wheel vertical velocity along wheel-fixed z-axis	m/s	
zddot		Wheel vertical acceleration along wheel-fixed z-axis	m/s ²	
Gndz		Ground displacement along negative of wheel-fixed z-axis (positive input produces wheel lift)	m	
GndFz		Vertical wheel force on ground along negative of wheel-fixed z-axis	N	
TirePrs		Tire pressure	Pa	
Fpatch		Tractive power applied from the axle		
PwrInfo	PwrTrnsfrd	PwrRoad	External torque applied by the axle to the wheel	W
		PwrAxlTrq	Vertical force applied to the wheel by the vehicle or suspension	W
		PwrFz	Tractive power loss	W
	PwrNotTrnsfrd	PwrSlip	Rolling resistance power	W
		PwrMyRoll	Braking power	W
		PwrMyBrk	Rolling viscous damping loss	W
		PwrMyb	Vertical damping power	W
	PwrStored	PwrFzDamp	Rate of change of vertical kinetic energy	W
		PwrStoredzdot	Rate of change of rotational kinetic energy	W
		PwrStoredq	Rate of change of stored sidewall potential energy	W
	PwrStoredFsFzSprng	Rate of change of gravitational potential energy	W	

Signal		Description	Units
	PwrStoredGrvty	Tractive power applied from the axle	W

F_x — Longitudinal axle force

scalar

Longitudinal force acting on axle, along body-fixed x-axis, in N. Positive force acts to move the vehicle forward.

Omega — Wheel angular velocity

scalar

Wheel angular velocity, about body-fixed y-axis, in rad/s.

z — Wheel vertical deflection

scalar

Wheel vertical deflection along wheel-fixed z-axis, in m.

Dependencies

To enable this port, set **Vertical Motion** to Mapped stiffness and damping.

zdot — Wheel vertical velocity

scalar

Wheel vertical velocity along wheel-fixed z-axis, in m/s.

Dependencies

To enable this port, set **Vertical Motion** to Mapped stiffness and damping.

Parameters

Block Options

Longitudinal Force — Select type

Magic Formula constant value (default) | Magic Formula pure longitudinal slip | Mapped force

The block models longitudinal force as a function of wheel slip relative to the road surface. To calculate the longitudinal force, specify one of these **Longitudinal Force** parameters.

Setting	Block Implementation
Magic Formula constant value	Magic Formula with constant coefficient for stiffness, shape, peak, and curvature.
Magic Formula pure longitudinal slip	Magic Formula with load-dependent coefficients that implement equations 4.E9 through 4.E18 in <i>Tire and Vehicle Dynamics</i> .
Mapped force	Lookup table that is a function of the normal force and wheel slip ratio.

Dependencies

Selecting	Enables These Parameters
Magic Formula constant value	Pure longitudinal peak factor, Dx Pure longitudinal shape factor, Cx Pure longitudinal stiffness factor, Bx Pure longitudinal curvature factor, Ex

Selecting	Enables These Parameters
<p>Magic Formula pure longitudinal slip</p>	<p>Cfx shape factor, PCX1</p> <p>Longitudinal friction at nominal normal load, PDX1</p> <p>Frictional variation with load, PDX2</p> <p>Frictional variation with camber, PDX3</p> <p>Longitudinal curvature at nominal normal load, PEX1</p> <p>Variation of curvature factor with load, PEX2</p> <p>Variation of curvature factor with square of load, PEX3</p> <p>Longitudinal curvature factor with slip, PEX4</p> <p>Longitudinal slip stiffness at nominal normal load, PKX1</p> <p>Variation of slip stiffness with load, PKX2</p> <p>Slip stiffness exponent factor, PKX3</p> <p>Horizontal shift in slip ratio at nominal normal load, PHX1</p> <p>Variation of horizontal slip ratio with load, PHX2</p> <p>Vertical shift in load at nominal normal load, PVX1</p> <p>Variation of vertical shift with load, PVX2</p> <p>Linear variation of longitudinal slip stiffness with tire pressure, PPX1</p> <p>Quadratic variation of longitudinal slip stiffness with tire pressure, PPX2</p> <p>Linear variation of peak longitudinal friction with tire pressure, PPX3</p> <p>Quadratic variation of peak longitudinal friction with tire pressure, PPX4</p> <p>Linear variation of longitudinal slip stiffness with tire pressure, PPX1</p> <p>Slip speed decay function scaling factor, lam_muV</p> <p>Brake slip stiffness scaling factor, lam_Kxkappa</p> <p>Longitudinal shape scaling factor, lam_Cx</p> <p>Longitudinal curvature scaling factor, lam_Ex</p>

Selecting	Enables These Parameters
	Longitudinal horizontal shift scaling factor, lam_Hx Longitudinal vertical shift scaling factor, lam_Vx
Mapped force	Slip ratio breakpoints, kappaFx Normal force breakpoints, FzFx Longitudinal force map, FxMap

Rolling Resistance – Select type

None (default) | Pressure and velocity | ISO 28580 | Magic Formula | Mapped torque

To calculate the rolling resistance torque, specify one of these **Rolling Resistance** parameters.

Setting	Block Implementation
None	None
Pressure and velocity	Method in <i>Stepwise Cooldown Methodology for Measuring Tire Rolling Resistance</i> . The rolling resistance is a function of tire pressure, normal force, and velocity.
ISO 28580	Method specified in ISO 28580:2018, <i>Passenger car, truck and bus tyre rolling resistance measurement method – Single point test and correlation of measurement results</i> .
Magic Formula	Magic formula equations from 4.E70 in <i>Tire and Vehicle Dynamics</i> . The magic formula is an empirical equation based on fitting coefficients.
Mapped torque	Lookup table that is a function of the normal force and spin axis longitudinal velocity.

Dependencies

Selecting	Parameters
Pressure and velocity	Velocity independent force coefficient, aMy Linear velocity force component, bMy Quadratic velocity force component, cMy Tire pressure exponent, alphaMy Normal force exponent, betaMy

Selecting	Parameters
ISO 28580	Parasitic losses force, Fpl Rolling resistance constant, Cr Thermal correction factor, Kt Measured temperature, Tmeas Parasitic losses force, Fpl Ambient temperature, Tamb
Magic Formula	Rolling resistance torque coefficient, QSY Longitudinal force rolling resistance coefficient, QSY2 Linear rotational speed rolling resistance coefficient, QSY3 Quartic rotational speed rolling resistance coefficient, QSY4 Camber squared rolling resistance torque, QSY5 Load based camber squared rolling resistance torque, QSY6 Normal load rolling resistance coefficient, QSY7 Pressure load rolling resistance coefficient, QSY8 Rolling resistance scaling factor, lam_My
Mapped torque	Spin axis velocity breakpoints, VxMy Normal force breakpoints, FzMy Rolling resistance torque map, MyMap

Brake Type – Select type

None | Disc | Drum | Mapped

There are four types of Longitudinal Wheel blocks. Each block implements a different brake type.

Block Name	Brake Type Setting	Brake Implementation
Longitudinal Wheel - No Brake	None	None
Longitudinal Wheel - Disc Brake	Disc	Brake that converts the brake cylinder pressure into a braking force.
Longitudinal Wheel - Drum Brake	Drum	Simplex drum brake that converts the applied force and brake geometry into a net braking torque.

Block Name	Brake Type Setting	Brake Implementation
Longitudinal Wheel - Mapped Brake	Mapped	Lookup table that is a function of the wheel speed and applied brake pressure.

Vertical Motion – Select type

None (default) | Mapped stiffness and damping

To calculate vertical motion, specify one of these **Vertical Motion** parameters.

Setting	Block Implementation
None	Block passes the applied chassis forces directly through to the rolling resistance and longitudinal force calculations.
Mapped stiffness and damping	Vertical motion depends on wheel stiffness and damping. Stiffness is a function of tire sidewall displacement and pressure. Damping is a function of tire sidewall velocity and pressure.

Selecting	Enables These Parameters	Creates These Output Ports
Mapped stiffness and damping	Wheel and unsprung mass, m Initial deflection, z₀ Initial velocity, z_{dot0} Gravitational acceleration, g Vertical deflection breakpoints, zFz Pressure breakpoints, pFz Force due to deflection, Fzz Vertical velocity breakpoints, zdotFz Force due to velocity, Fzzdot Ground displacement, Gndz Input ground displacement	z zdot

Longitudinal scaling factor, lam_x – Friction scaling factor

1 (default)

Longitudinal friction scaling factor, dimensionless.

Dependencies

To enable this parameter, clear **Input friction scale factor**.

Input friction scale factor – Selection

Off (default)

Create input port for longitudinal friction scaling factor.

Dependencies

Selecting this parameter:

- Creates input port `lam_mux`.
- Disables parameter **Longitudinal scaling factor, lam_x**.

Wheel Dynamics

Axle viscous damping coefficient, br – Damping

0.001 (default) | scalar

Axle viscous damping coefficient, br , in N·m·s/rad.

Wheel inertia, Iyy – Inertia

0.8 (default) | scalar

Wheel inertia, in kg·m².

Wheel initial angular velocity, omegao – Wheel speed

0 (default) | scalar

Initial angular velocity of wheel, along body-fixed y-axis, in rad/s.

Relaxation length, Lrel – Relaxation length

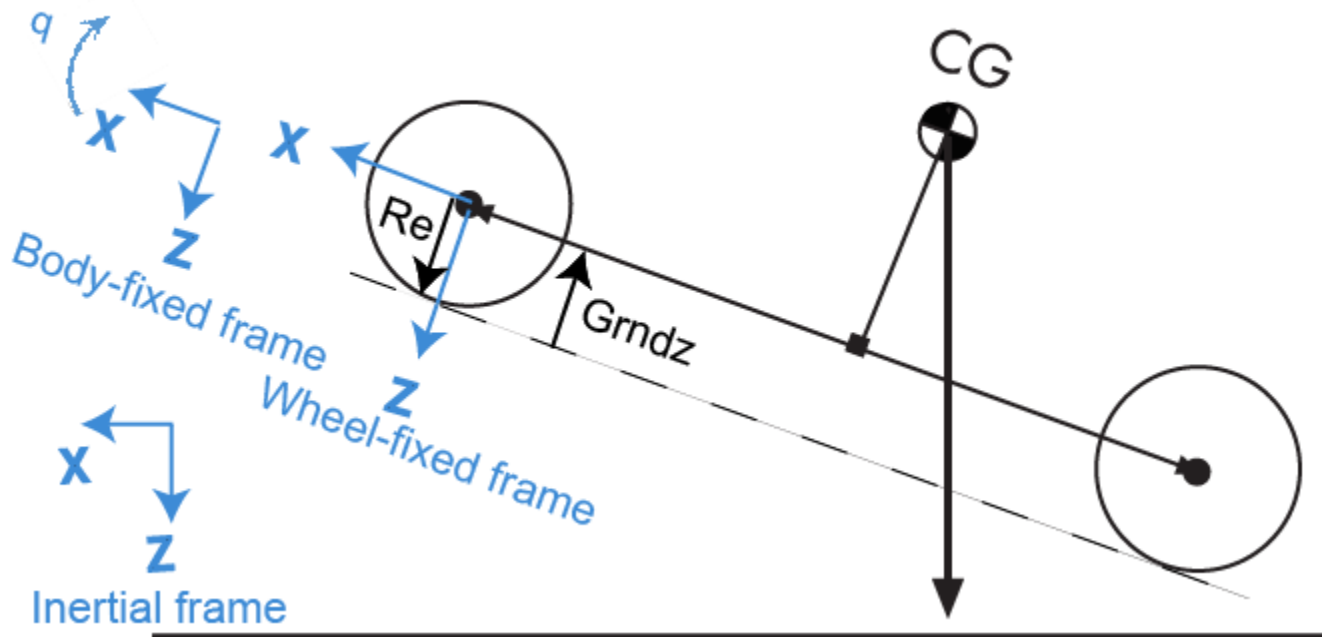
0.5 (default) | scalar

Wheel relaxation length, in m.

Loaded radius, Re – Loaded radius

0.3 (default) | scalar

Loaded wheel radius, Re , in m.



Unloaded radius, UNLOADED_RADIUS – Unloaded radius

0.4 (default) | scalar

Unloaded wheel radius, in m.

Dependencies

To create this parameter, set **Rolling Resistance** to Pressure and velocity or Magic Formula.

Nominal longitudinal speed, LONGVL – Speed

16 (default) | scalar

Nominal longitudinal speed along body-fixed x-axis, in m/s.

Dependencies

To enable this parameter, set **Longitudinal Force** to Magic Formula pure longitudinal slip.

Nominal camber angle, gamma – Camber

0 (default) | scalar

Nominal camber angle, in rad.

Dependencies

To enable this parameter, set either:

- **Longitudinal Force** to Magic Formula pure longitudinal slip.
- **Rolling Resistance** to Magic Formula.

Nominal pressure, NOMPRES – Pressure

220000 (default) | scalar

Nominal pressure, in Pa.

Dependencies

To enable this parameter, set either:

- **Longitudinal Force** to Magic Formula pure longitudinal slip.
- **Rolling Resistance** to Magic Formula.

Pressure, press – Pressure

220000 (default) | scalar

Pressure, in Pa.

Dependencies

To enable this parameter:

- Set one of these:
 - **Longitudinal Force** to Magic Formula pure longitudinal slip.
 - **Rolling Resistance** to Pressure and velocity or Magic Formula.
 - **Vertical Motion** to Mapped stiffness and damping.
- On the **Wheel Dynamics** pane, clear **Input tire pressure**.

Longitudinal

Magic Formula Constant Value

Pure longitudinal peak factor, Dx – Factor

1 (default) | scalar

Pure longitudinal peak factor, dimensionless.

The coefficients are based on empirical tire data. These values are typical sets of constant Magic Formula coefficients for common road conditions.

Surface	B	C	D	E
Dry tarmac	10	1.9	1	0.97
Wet tarmac	12	2.3	0.82	1
Snow	5	2	0.3	1
Ice	4	2	0.1	1

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula constant value.

Pure longitudinal shape factor, Cx – Factor

1.65 (default) | scalar

Pure longitudinal shape factor, dimensionless.

The coefficients are based on empirical tire data. These values are typical sets of constant Magic Formula coefficients for common road conditions.

Surface	B	C	D	E
Dry tarmac	10	1.9	1	0.97
Wet tarmac	12	2.3	0.82	1
Snow	5	2	0.3	1
Ice	4	2	0.1	1

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula constant value.

Pure longitudinal stiffness factor, Bx – Factor

10 (default) | scalar

Pure longitudinal stiffness factor, dimensionless.

The coefficients are based on empirical tire data. These values are typical sets of constant Magic Formula coefficients for common road conditions.

Surface	B	C	D	E
Dry tarmac	10	1.9	1	0.97
Wet tarmac	12	2.3	0.82	1
Snow	5	2	0.3	1
Ice	4	2	0.1	1

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula constant value.

Pure longitudinal curvature factor, Ex – Factor

0.01 (default) | scalar

Pure longitudinal curvature factor, dimensionless.

The coefficients are based on empirical tire data. These values are typical sets of constant Magic Formula coefficients for common road conditions.

Surface	B	C	D	E
Dry tarmac	10	1.9	1	0.97
Wet tarmac	12	2.3	0.82	1
Snow	5	2	0.3	1
Ice	4	2	0.1	1

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula constant value.

Magic Formula Pure Longitudinal Slip**Cfx shape factor, PCX1 – Factor**

1.6 (default) | scalar

Cfx shape factor, PCX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal friction at nominal normal load, PDX1 – Factor

1 (default) | scalar

Longitudinal friction at nominal normal load, PDX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Frictional variation with load, PDX2 – Factor

-0.08 (default) | scalar

Frictional variation with load, PDX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Frictional variation with camber, PDX3 – Factor

0 (default) | scalar

Frictional variation with camber, PDX3, 1/rad².

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal curvature at nominal normal load, PEX1 – Factor

0.112 (default) | scalar

Longitudinal curvature at nominal normal load, PEX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Variation of curvature factor with load, PEX2 – Factor

0.313 (default) | scalar

Variation of curvature factor with load, PEX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Variation of curvature factor with square of load, PEX3 – Factor

0 (default) | scalar

Variation of curvature factor with square of load, PEX3, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal curvature factor with slip, PEX4 – Factor

0.0016 (default) | scalar

Longitudinal curvature factor with slip, PEX4, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal slip stiffness at nominal normal load, PKX1 – Factor

21.7 (default) | scalar

Longitudinal slip stiffness at nominal normal load, PKX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Variation of slip stiffness with load, PKX2 – Factor

13.77 (default) | scalar

Variation of slip stiffness with load, PKX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Slip stiffness exponent factor, PKX3 – Factor

-0.412 (default) | scalar

Slip stiffness exponent factor, PKX3, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Horizontal shift in slip ratio at nominal normal load, PHX1 – Factor

2.1585E-4 (default) | scalar

Horizontal shift in slip ratio at nominal normal load, PHX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Variation of horizontal slip ratio with load, PHX2 – Factor

0.00115 (default) | scalar

Variation of horizontal slip ratio with load, PHX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Vertical shift in load at nominal normal load, PVX1 – Factor

1.5973E-5 (default) | scalar

Vertical shift in load at nominal normal load, PVX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Variation of vertical shift with load, PVX2 – Factor

1.043E-4 (default) | scalar

Variation of vertical shift with load, PVX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Linear variation of longitudinal slip stiffness with tire pressure, PPX1 – Factor

-0.3489 (default) | scalar

Linear variation of longitudinal slip stiffness with tire pressure, PPX1, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Quadratic variation of longitudinal slip stiffness with tire pressure, PPX2 – Factor

0.382 (default) | scalar

Quadratic variation of longitudinal slip stiffness with tire pressure, PPX2, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Linear variation of peak longitudinal friction with tire pressure, PPX3 – Factor

-0.09634 (default) | scalar

Linear variation of peak longitudinal friction with tire pressure, PPX3, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Quadratic variation of peak longitudinal friction with tire pressure, PPX4 – Factor

0.06447 (default) | scalar

Quadratic variation of peak longitudinal friction with tire pressure, PPX4, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Slip speed decay function scaling factor, lam_muV – Factor

1 (default) | scalar

Slip speed decay function scaling factor, lam_muV, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Brake slip stiffness scaling factor, lam_Kxkappa – Factor

1 (default) | scalar

Brake slip stiffness scaling factor, lam_Kxkappa, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal shape scaling factor, lam_Cx – Factor

1 (default) | scalar

Longitudinal shape scaling factor, lam_Cx, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal curvature scaling factor, lam_Ex — Factor

0 (default) | scalar

Longitudinal curvature scaling factor, lam_Ex, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal horizontal shift scaling factor, lam_Hx — Factor

1 (default) | scalar

Longitudinal horizontal shift scaling factor, lam_Hx, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Longitudinal vertical shift scaling factor, lam_Vx — Factor

1 (default) | scalar

Longitudinal vertical shift scaling factor, lam_Vx, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Magic Formula pure longitudinal slip.

Mapped Force

Slip ratio breakpoints, kappaFx — Breakpoints

vector

Slip ratio breakpoints, dimensionless.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Mapped force.

Normal force breakpoints, FzFx — Breakpoints

vector

Normal force breakpoints, N.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Mapped force.

Longitudinal force map, FxMap — Lookup table

array

Longitudinal force versus slip ratio and normal force, N.

Dependencies

To create this parameter, select the **Longitudinal Force** parameter Mapped force.

Rolling Resistance**Pressure and Velocity****Velocity independent force coefficient, aMy – Force coefficient**

8e-4 (default) | scalar

Velocity-independent force coefficient, a , in s/m.**Dependencies**To create this parameter, select the **Rolling Resistance** parameter Pressure and velocity.**Linear velocity force component, bMy – Force component**

.001 (default) | scalar

Linear velocity force component, b , in s/m.**Dependencies**To create this parameter, select the **Rolling Resistance** parameter Pressure and velocity.**Quadratic velocity force component, cMy – Force component**

1.6e-4 (default) | scalar

Quadratic velocity force component, c , in s²/m².**Dependencies**To create this parameter, select the **Rolling Resistance** parameter Pressure and velocity.**Tire pressure exponent, alphaMy – Pressure exponent**

-0.003 (default) | scalar

Tire pressure exponent, α , dimensionless.**Dependencies**To create this parameter, select the **Rolling Resistance** parameter Pressure and velocity.**Normal force exponent, betaMy – Force exponent**

0.97 (default) | scalar

Normal force exponent, β , dimensionless.**Dependencies**To create this parameter, select the **Rolling Resistance** parameter Pressure and velocity.**ISO 28580****Parasitic losses force, Fpl – Force loss**

10 (default) | scalar

Parasitic force loss, F_{pl} , in N.**Dependencies**To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Rolling resistance constant, Cr – Constant

1e-3 (default) | scalar

Rolling resistance constant, C_r , in N/kN. ISO 28580 specifies the rolling resistance unit as one newton of tractive resistance for every kilonewtons of normal load.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Thermal correction factor, Kt – Correction factor

.008 (default) | scalar

Thermal correction factor, K_t , in 1/degC.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Measured temperature, Tmeas – Temperature during testing

298.15 (default) | scalar

Measured ambient temperature, T_{meas} , near tire during tire testing, in K.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Ambient temperature, Tamb – Temperature

298.15 (default) | scalar

Measured ambient temperature, T_{amb} , near tire in application environment, in K. For example, the measured ambient temperature is the ambient temperature near the tire when the vehicle is on the road.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Input ambient temperature – Selection

off (default) | on

Select to create input port Tamb to input the measured ambient temperature.

The measured ambient temperature, T_{amb} , is the temperature near tire in application environment, in K. For example, the measured ambient temperature is the ambient temperature near the tire when the vehicle is on the road.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Magic Formula**Rolling resistance torque coefficient, QSY1 – Torque coefficient**

0.007 (default) | scalar

Rolling resistance torque coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Longitudinal force rolling resistance coefficient, QSY2 – Force resistance coefficient

0 (default) | scalar

Longitudinal force rolling resistance coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Linear rotational speed rolling resistance coefficient, QSY3 – Linear speed coefficient

0.0015 (default) | scalar

Linear rotational speed rolling resistance coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Quartic rotational speed rolling resistance coefficient, QSY4 – Quartic speed coefficient

8.5e-05 (default) | scalar

Quartic rotational speed rolling resistance coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Camber squared rolling resistance torque, QSY5 – Camber resistance torque

0 (default) | scalar

Camber squared rolling resistance torque, in $1/\text{rad}^2$.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Load based camber squared rolling resistance torque, QSY6 – Load resistance torque

0 (default) | scalar

Load based camber squared rolling resistance torque, in $1/\text{rad}^2$.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Normal load rolling resistance coefficient, QSY7 – Normal resistance coefficient

0.9 (default) | scalar

Normal load rolling resistance coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Pressure load rolling resistance coefficient, QSY8 – Pressure resistance coefficient

-0.4 (default) | scalar

Pressure load rolling resistance coefficient, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Rolling resistance scaling factor, lam_My – Scale

1 (default) | scalar

Rolling resistance scaling factor, dimensionless.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Magic Formula.

Mapped**Spin axis velocity breakpoints, VxMy – Breakpoints**

-20:1:20 (default) | vector

Spin axis velocity breakpoints, in m/s.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Mapped torque.

Normal force breakpoints, FzMy – Breakpoints

0:200:1e4 (default) | vector

Normal force breakpoints, in N.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Mapped torque.

Rolling resistance torque map, MyMap – Lookup table

array

Rolling resistance torque versus axle speed and normal force, in N·m.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter Mapped torque.

Brake**Static friction coefficient, mu_static – Static friction**

.3 (default) | scalar

Static friction coefficient, specified as a scalar, dimensionless.

Dependencies

To enable this parameter, for the **Brake Type** parameter, specify one of these types:

- Disc
- Drum
- Mapped

Kinetic friction coefficient, mu_kinetic – Kinetic friction

.2 (default) | scalar

Kinematic friction coefficient, specified as a scalar, dimensionless.

Dependencies

To enable this parameter, for the **Brake Type** parameter, specify one of these types:

- Disc
- Drum
- Mapped

Disc**Disc brake actuator bore, disc_abore – Bore distance**

.05 (default) | scalar

Disc brake actuator bore, specified as a scalar, in m.

Dependencies

To enable the disc brake parameters, select Disc for the **Brake Type** parameter.

Brake pad mean radius, Rm – Radius

.177 (default) | scalar

Brake pad mean radius, specified as a scalar, in m.

Dependencies

To enable the disc brake parameters, select Disc for the **Brake Type** parameter.

Number of brake pads, num_pads – Count

2 (default) | scalar

Number of brake pads, specified as a scalar, dimensionless.

Dependencies

To enable the disc brake parameters, select Disc for the **Brake Type** parameter.

Drum**Drum brake actuator bore, disc_abore – Bore distance**

0.0508 (default) | scalar

Drum brake actuator bore, specified as a scalar, in m.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Shoe pin to drum center distance, drum_a – Distance

0.123 (default) | scalar

Shoe pin to drum center distance, in m.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Shoe pin center to force application point distance, drum_c – Distance

0.212 (default) | scalar

Shoe pin center to force application point distance, in m.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Drum internal radius, drum_r – Radius

0.15 (default) | scalar

Drum internal radius, in m.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Shoe pin to pad start angle, drum_theta1 – Angle

0 (default) | scalar

Shoe pin to pad start angle, in deg.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Shoe pin to pad end angle, drum_theta2 – Angle

126 (default) | scalar

Shoe pin to pad end angle, in deg.

Dependencies

To enable the drum brake parameters, select Drum for the **Brake Type** parameter.

Mapped**Brake actuator pressure breakpoints, brake_p_bpt – Breakpoints**

vector

Brake actuator pressure breakpoints, in bar.

Dependencies

To enable the mapped brake parameters, select Mapped for the **Brake Type** parameter.

Wheel speed breakpoints, `brake_n_bpt` – Breakpoints vector

Wheel speed breakpoints, in rpm.

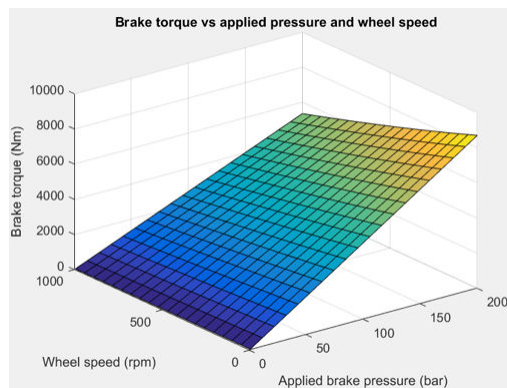
Dependencies

To enable the mapped brake parameters, select Mapped for the **Brake Type** parameter.

Brake torque map, `f_brake_t` – Lookup table array

The lookup table for the brake torque, $f_{brake}(P, N)$, is a function of applied brake pressure and wheel speed, where:

- T is brake torque, in N·m.
- P is applied brake pressure, in bar.
- N is wheel speed, in rpm.



Dependencies

To enable the mapped brake parameters, select Mapped for the **Brake Type** parameter.

Vertical

Nominal normal force, `FNOMIN` – Force 2000 (default) | scalar

Nominal rated wheel load along wheel-fixed z-axis, in N.

Dependencies

To enable this parameter, set either:

- **Longitudinal Force** to Magic Formula pure longitudinal slip.
- **Rolling Resistance** to Magic Formula.

Nominal rated load scaling factor, `lam_Fzo` – Factor 1 (default) | scalar

Nominal rated load scaling factor, dimensionless. Used to scale the normal for specific applications and load conditions.

Dependencies

To enable this parameter, set **Longitudinal Force** to Magic Formula pure longitudinal slip.

Wheel and unsprung mass, m – Mass

10 (default) | scalar

Wheel and unsprung mass, in kg. Used in the vertical motion calculations.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Initial deflection, zo – Deflection

0 (default) | scalar

Initial axle displacement along wheel-fixed z-axis, in m.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Initial velocity, zdoto – Velocity

0 (default) | scalar

Initial axle velocity along wheel-fixed z-axis, in m.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Gravitational acceleration, g – Gravity

9.81 (default) | scalar

Gravitational acceleration, in m/s².

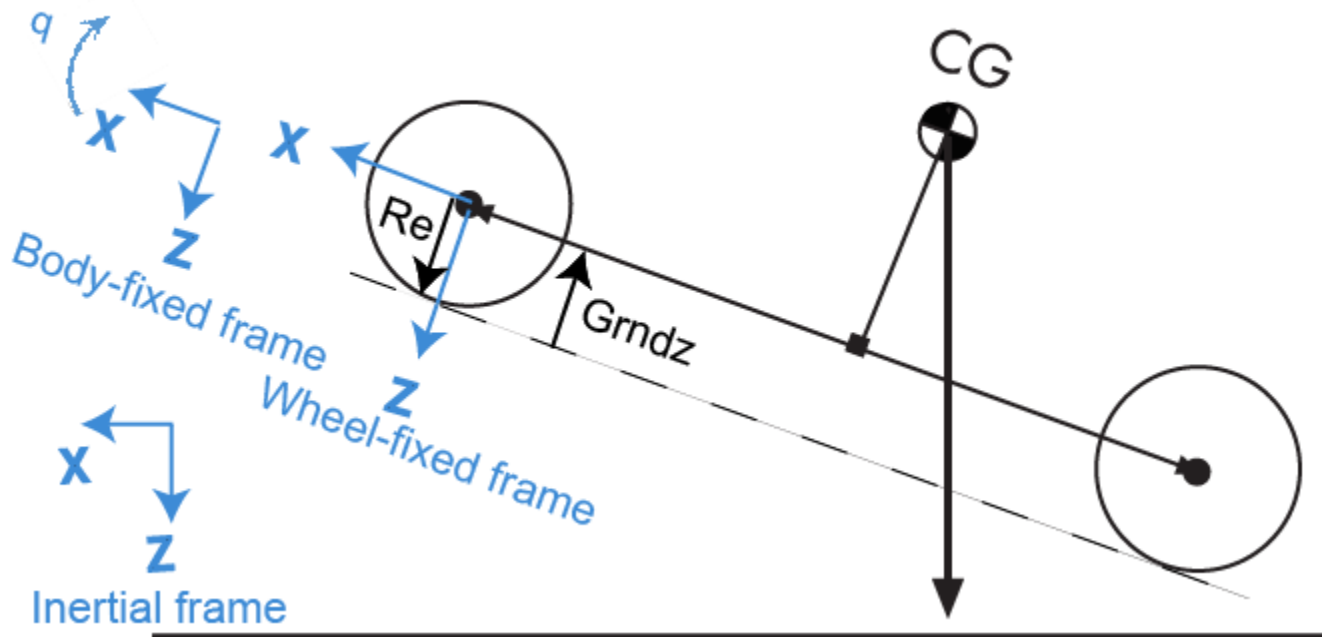
Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Ground displacement, Gndz – Displacement

0 (default) | scalar

Ground displacement, Grndz, along negative wheel-fixed z-axis, in m.

**Dependencies**

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Mapped Stiffness and Damping**Vertical deflection breakpoints, zFz – Breakpoints**

[0 .01 .1] (default) | vector

Vector of sidewall deflection breakpoints corresponding to the force table, in m.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Pressure breakpoints, pFz – Breakpoints

[10000 1000000] (default) | vector

Vector of pressure data points corresponding to the force table, in Pa.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Force due to deflection, Fzz – Force

[0 1e3 1e4; 0 1e4 1e5] (default) | vector

Force due to sidewall deflection and pressure along wheel-fixed z-axis, in N.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Vertical velocity breakpoints, zdotFz – Breakpoints

[-20 0 20] (default) | scalar

Vector of sidewall velocity breakpoints corresponding to the force due to velocity table, in m.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Force due to velocity, Fzzdot – Force

[500 0 -500;250 0 -250] (default) | array

Force due to sidewall velocity and pressure along wheel-fixed z-axis, in N.

Dependencies

To enable this parameter, set **Vertical Motion** to Mapped stiffness and damping.

Simulation Setup**Minimum normal force, FZMIN – Force**

0 (default) | scalar

Minimum normal force, in N. Used with all vertical force calculations.

Maximum normal force, FZMAX – Force

10000 (default) | scalar

Maximum normal force, in N. Used with all vertical force calculations.

Max allowable slip ratio (absolute), kappamax – Ratio

1.5 (default) | scalar

Maximum allowable absolute slip ratio, dimensionless.

Velocity tolerance used to handle low velocity situations, VXL0W – Tolerance

1 (default) | scalar

Velocity tolerance used to handle low-velocity situations, in m/s.

Minimum ambient temperature, TMIN – Tmin

0 (default) | scalar

Minimum ambient temperature, T_{MIN} , in K.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Maximum ambient temperature, TMAX – Tmax

400 (default) | scalar

Maximum ambient temperature, T_{MAX} , in K.

Dependencies

To create this parameter, select the **Rolling Resistance** parameter ISO 28580.

Version History

Introduced in R2017a

References

- [1] Highway Tire Committee. *Stepwise Coastdown Methodology for Measuring Tire Rolling Resistance*. Standard J2452_199906. Warrendale, PA: SAE International, June 1999.
- [2] Pacejka, H. B. *Tire and Vehicle Dynamics*. 3rd ed. Oxford, United Kingdom: SAE and Butterworth-Heinemann, 2012.
- [3] Schmid, Steven R., Bernard J. Hamrock, and Bo O. Jacobson. "Chapter 18: Brakes and Clutches." *Fundamentals of Machine Elements, SI Version*. 3rd ed. Boca Raton, FL: CRC Press, 2014.
- [4] Shigley, Joseph E., and Larry Mitchel. *Mechanical Engineering Design*. 4th ed. New York, NY: McGraw Hill, 1983.
- [5] ISO 28580:2018. *Passenger car, truck and bus tyre rolling resistance measurement method -- Single point test and correlation of measurement results*. ISO (International Organization for Standardization), 2018.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

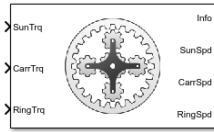
See Also

Drive Cycle Source | Longitudinal Driver

Planetary Gear

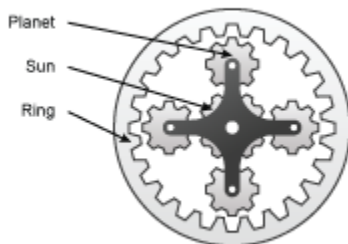
Ideal planetary gear with sun, ring, and carrier

Library: Powertrain Blockset / Drivetrain / Couplings



Description

The Planetary Gear block implements an ideal planetary gear coupling consisting of a rigidly coupled sun, ring, and carrier gears. The block calculates the dynamic response to the sun, carrier, and ring input torques.



In fuel economy and powertrain studies, you can use the Planetary Gear block as a power-split device by coupling it to common driveline elements such as transmissions, engines, clutches, and differentials.

These equations of motion represent the dynamic response of the planetary gear.

$$\dot{\omega}_s J_s = \dot{\omega}_s b_s + T_s + T_{ps}$$

$$\dot{\omega}_c J_c = \dot{\omega}_c b_c + T_c + T_{pc}$$

$$\dot{\omega}_r J_r = \dot{\omega}_r b_r + T_r + T_{pr}$$

$$\dot{\omega}_p J_p = \dot{\omega}_p b_p + T_{rp} + T_{sp} + T_{cp}$$

To reduce the equations of motion, the block uses these kinematic and geometric constraints.

$$\omega_c r_c = r_s \omega_s + r_p \omega_p$$

$$\omega_r r_r = r_c \omega_c + r_p \omega_p$$

$$r_c = r_s + r_p$$

$$r_r = r_c + r_p$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrSun	Sun gear applied power $\omega_s T_s$
	<ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrCarr	Carrier gear applied power $\omega_c T_c$
		PwrRing	Ring gear applied power $\omega_r T_r$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrDampLoss	Mechanical damping loss $-(b_s \omega_s^2 + b_c \omega_c^2 + b_r \omega_r^2 + b_p \omega_p^2)$
PwrStored — Stored energy rate of change	PwrStoredPlntry	Rate change in rotational kinetic energy $\dot{\omega}_s \omega_s J_s + \dot{\omega}_c \omega_c J_c + \dot{\omega}_r \omega_r J_r + \dot{\omega}_p \omega_p J_p$	
<ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 			

The equations use these variables.

$\omega_c, \omega_p, \omega_r, \omega_s$	Carrier, planet, ring, and sun gear angular speed
r_c, r_p, r_r, r_s	Carrier, planet, ring, and sun gear angular radius
J_c, J_p, J_r, J_s	Carrier, planet, ring, and sun gear inertia
b_c, b_p, b_r, b_s	Carrier, planet, ring, and sun gear damping
T_c, T_p, T_r, T_s	Applied carrier, planet, ring, and sun gear torque

T_{ps}	Torque applied from planet gear on sun gear
T_{pc}	Torque applied from planet gear on carrier gear
T_{pr}	Torque applied from planet gear on ring gear
T_{rp}	Torque applied from ring gear on planet gear
T_{sp}	Torque applied from sun gear on planet gear
T_{cp}	Torque applied from carrier gear on planet gear

Ports

Input

SunTrq — Sun gear applied torque

scalar

Sun gear input torque, T_s , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

CarrTrq — Carrier gear applied torque

scalar

Carrier gear input torque, T_c , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

RingTrq — Ring gear applied torque

scalar

Ring gear applied torque, T_r , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

C — Carrier gear angular speed and torque

two-way connector port

Carrier gear angular speed, ω_c , in rad/s. Carrier gear applied torque, T_c , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Two-way connection.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
Sun	SunTrq	Sun gear applied torque	N·m	
	SunSpd	Sun gear angular speed	rad/s	
Carr	CarrTrq	Carrier gear applied torque	N·m	
	CarrSpd	Carrier gear angular speed	rad/s	
Ring	RingTrq	Ring gear applied torque	N·m	
PwrInfo	PwrTrnsfrd	PwrSun	Sun gear applied power	W
		PwrCarr	Carrier gear applied power	W
		PwrRing	Ring gear applied power	W
	PwrNotTrnsfrd	PwrDampLoss	Mechanical damping loss	W
	PwrStored	PwrStoredPlntry	Rate change in rotational kinetic energy	W

SunSpd – Sun gear angular speed

scalar

Sun gear angular speed, ω_s , in rad/s.**Dependencies**To create this port, for **Port Configuration**, select Simulink.**CarrSpd – Carrier gear angular speed**

scalar

Carrier gear angular speed, ω_c , in rad/s.**Dependencies**To create this port, for **Port Configuration**, select Simulink.**RingSpd – Ring gear angular speed**

scalar

Ring gear angular speed, ω_r , in rad/s.**Dependencies**To create this port, for **Port Configuration**, select Simulink.**S – Sun gear angular speed and torque**

two-way connector port

Sun gear angular speed, ω_s , in rad/s. Sun gear applied torque, T_s , in N·m.**Dependencies**To create this port, for **Port Configuration**, select Two-way connection.**R – Ring gear angular speed and torque**

two-way connector port

Ring gear angular speed, ω_r , in rad/s. Ring gear applied torque, T_r , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Two-way connection.

Parameters**Block Options****Port Configuration – Specify configuration**

Simulink (default) | Two-way connection

Specify the port configuration.

Dependencies

Specifying Simulink creates these ports:

- SunTrq
- CarrTrq
- RingTrq
- SunSpd
- CarrSpd
- RingSpd

Specifying Two-way connection creates these ports:

- C
- S
- R

Sun to planet ratio, Nsp – Ratio

30/23 (default) | scalar

Sun-to-planet gear ratio, dimensionless.

Sun to ring ratio, Nsr – Ratio

30/78 (default) | scalar

Sun-to-ring gear ratio, dimensionless.

Sun inertia, Js – Inertia

.003 (default) | scalar

Sun gear inertia, J_s , in kg·m².

Planet inertia, Jp – Inertia

.001 (default) | scalar

Planet gear inertia, J_p , in kg·m².

Ring inertia, Jr – Inertia

.01 (default) | scalar

Ring gear inertia, J_r , in $\text{kg}\cdot\text{m}^2$.

Carrier inertia, J_c – Inertia

.002 (default) | scalar

Carrier gear inertia, J_c , in $\text{kg}\cdot\text{m}^2$.

Sun viscous damping, b_s – Damping

.001 (default) | scalar

Sun gear viscous damping, b_s , $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Ring viscous damping, b_r – Damping

.001 (default) | scalar

Ring gear viscous damping, b_r , $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Planet viscous damping, b_p – Damping

.001 (default) | scalar

Planet gear viscous damping, b_p , $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Carrier viscous damping, b_c – Damping

.001 (default) | scalar

Carrier gear viscous damping, b_c , $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Initial sun velocity, ws_o – Angular speed

0 (default) | scalar

Initial sun gear angular speed, in rad/s .

Initial carrier velocity, wc_o – Angular speed

0 (default) | scalar

Initial carrier gear angular speed, in rad/s .

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

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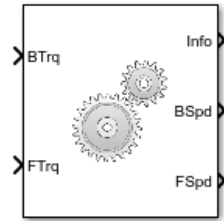
See Also

Disc Clutch | Gearbox | Rotational Inertia | Torque Converter | Torsional Compliance

Gearbox

Ideal rotational gearbox

Library: Powertrain Blockset / Drivetrain / Couplings



Description

The Gearbox block implements an ideal rotational gearbox. The block uses the gear inertias and damping to calculate the velocity response to the base and follower gear pair input torques.

In fuel economy and powertrain efficiency studies, you can use the Gearbox block to model ideal gear coupling and the power transfer between common driveline elements such as transmissions, engines, clutches, and differentials.

The Gearbox block uses these equations to approximate the transmission dynamics.

$$\dot{\omega}_B J_B = \omega_B b_B + \eta N T_F$$

$$\dot{\omega}_F J_F = \omega_F b_F + \eta T_F$$

This constraint equation reduces the system to a one DOF system.

$$\omega_B = N \omega_F$$

To express the ideal torque transfer, the block uses this relationship.

$$\eta N T_B + T_F = 0$$

Efficiency

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.

Setting	Implementation
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrBase	Mechanical power from base shaft	P_{Base}	$P_{Base} = \eta T_B \omega_B$
	<ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrFlwr	Mechanical power from follower shaft	P_{Flwr}	$P_{Flwr} = \eta T_F \omega_F$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrMechLoss	Total power loss	P_{ng}	$P_{ng} = - (P_t + P_d) + P_s$
	<ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrDampLoss	Power loss due to damping	P_d	$P_d = - (b_F \omega_F ^2 + b_B \omega_B ^2)$
PwrStored — Stored energy rate of change	PwrStoredShft	Rate change of stored internal kinetic energy	P_s	$P_s = (\omega_B \dot{\omega}_B J_B + \omega_F \dot{\omega}_F J_F)$	
<ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 					

The equations use these variables.

T_B	Base gear input torque
T_F	Follower gear output torque
ω_B	Base gear angular velocity
ω_F	Follower gear angular velocity
J_B	Base gear rotational inertia
J_F	Follower gear rotational inertia
b_B	Base gear rotational viscous damping
b_F	Follower gear rotational viscous damping
N	Torque transmission gear ratio
η	Gear efficiency
P_t	Total power
P_d	Power loss due to damping
P_s	Rate change of stored internal kinetic energy

Ports

Input

BTrq — Base gear input torque

scalar

Base gear input torque, T_B , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

FTrq — Follower gear output torque

scalar

Follower gear output torque, T_F , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

B — Base gear angular velocity and torque

two-way connector port

Base gear angular velocity, ω_B , in rad/s. Base gear torque, T_B , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Two-way connection.

AirTemp — Ambient air temperature

scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this port:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Select **Input ambient temperature**.

Output**Info — Bus signal**

bus

Bus signal containing these block calculations.

Signal			Description	Variable	Units
Base	BaseTrq		Base gear input torque	T_B	N·m
	BaseSpd		Base gear angular velocity	ω_B	rad/s
Flwr	FlwrTrq		Follower gear torque	T_F	N·m
	FlwrSpd		Follower gear angular velocity	ω_F	rad/s
PwrInfo	PwrTrnsfrd	PwrBase	Mechanical power from base shaft	P_{Base}	W
		PwrFlwr	Mechanical power from follower shaft	P_{Flwr}	W
	PwrNotTrnsfrd	PwrMechLoss	Total gear power loss	P_{ng}	W
		PwrDampLoss	Power loss due to damping	P_d	W
	PwrStored	PwrStoredShft	Rate change of stored internal kinetic energy	P_s	W

BSpd — Input gear angular velocity

scalar

Base gear angular velocity, ω_B , in rad/s.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

FSpd — Output gear angular velocity

scalar

Follower gear angular velocity, ω_F , in rad/s.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

F – Output gear angular velocity and torque

two-way connector port

Follower gear angular velocity, ω_F , in rad/s. Follower gear torque, T_F , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Two-way connection.

Parameters

Block Options

Port Configuration – Specify configuration

Simulink (default) | Two-way connection

Specify the port configuration.

Dependencies

Specifying Simulink creates these ports:

- BSpd
- FSpd
- BTrq
- FTrq

Specifying Two-way connection creates these ports:

- B
- F

Efficiency factors – Specify configuration

Constant (default) | Driveshaft torque, speed and temperature

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.

Setting	Implementation
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Interpolation method – Method

Flat | Nearest | Linear point-slope | Linear Lagrange | Cubic spline

For more information, see “Interpolation Methods”.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Output shaft rotates in same direction as input – Rotation

off (default) | on

Select to specify that the output shaft rotates in the same direction as the input.

Input ambient temperature – Create input port

off (default) | on

Select to create input port AirTemp for the ambient air temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Input to output gear ratio, N – Ratio

2 (default) | scalar

Base-to-follower gear ratio, dimensionless.

Input shaft inertia, J1 – Inertia

.01 (default) | scalar

Base shaft inertia, in $\text{kg}\cdot\text{m}^2$.

Output shaft inertia, J2 – Inertia

.01 (default) | scalar

Follower shaft inertia, in $\text{kg}\cdot\text{m}^2$.

Input shaft damping, b1 – Damping

.001 (default) | scalar

Base viscous shaft damping, in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Output shaft damping, b2 – Damping

.001 (default) | scalar

Follower viscous shaft damping, in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Input shaft initial velocity, w1_o – Initial velocity

0 (default) | scalar

Base shaft initial velocity, in rad/s .

Efficiency**Constant efficiency factor, eta – Efficiency**

1 (default) | scalar

Constant efficiency, η .

Dependencies

To enable this parameter, set **Efficiency factors** to Constant.

Efficiency lookup table, eta_tbl – Lookup table

M-by-N-by-L array

Dimensionless array of values for efficiency as a function of:

- M input torques
- N input speed
- L air temperatures

Each value specifies the efficiency for a specific combination of torque, speed, and temperature. The array size must match the dimensions defined by the torque, speed, and temperature breakpoint vectors.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency torque breakpoints, Trq_bpts – Torque breakpoints

[25, 50, 75, 100, 150, 200, 250] (default) | 1-by-M vector

Vector of input torque, breakpoints for efficiency, in $\text{N}\cdot\text{m}$.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency speed breakpoints, omega_bpts — Speed breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | 1-by-N vector

Vector of speed, breakpoints for efficiency, in rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency temperature breakpoints, Temp_bpts — Temperature breakpoints

[290 358] (default) | 1-by-L vector

Vector of ambient temperature breakpoints for efficiency, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Air temperature, Tair — Ambient air temperature

297.15 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Clear **Input ambient temperature**.

Version History

Introduced in R2017a

Extended Capabilities

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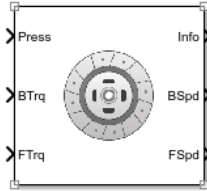
See Also

Disc Clutch | Planetary Gear | Rotational Inertia | Torque Converter | Torsional Compliance

Disc Clutch

Idealized disc clutch coupler

Library: Powertrain Blockset / Drivetrain / Couplings



Description

The Disc Clutch block implements an idealized disc clutch coupler. The block couples the rotary input and output shafts through an idealized friction model. To determine the output torque, the block uses friction parameters, relative slip velocity, and applied input pressure.

In fuel economy and powertrain efficiency studies, you can use the Disc Clutch block to model the mechanical power transfer between common driveline elements such as transmissions, engines, and differentials.

To approximate the torque response, the Disc Clutch block implements friction and dynamic models that depend on the clutch lockup condition. The block determines the locked or unlocked condition based on an idealized dry clutch friction model. This table summarizes the logic the block uses to determine the clutch condition.

Clutch Condition	When
Unlocked	$\omega_i \neq \omega_o$ or $T_{fmax} < \left \frac{J_o T_i - (J_o b_i - J_i b_o) \omega_{i/o}}{J_o + J_i} \right $
Locked	$\omega_i = \omega_o$ and $T_{fmax} < \left T_i - \frac{J_i (b_i + b_o) \omega_i}{J_o + J_i} + b_o \omega_i \right $

This table summarizes the friction and dynamic models that the block uses for locked or unlocked clutch conditions.

Clutch Condition	Friction Model	Dynamic Model
Unlocked	$T_{fmax} = T_k$ where, $T_k = N_{disc} P_c A_{eff} R_{eff} \mu_k \tanh[4(\omega_i - \omega_o)]$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$ and $P_c = \max(P_c - P_{eng}, 0)$	$\dot{\omega}_i J_i = T_i - T_f - \omega_i b_i$ $\dot{\omega}_o J_o = T_f + T_o - \omega_o b_o$
Locked	$T_{fmax} = T_s$ where, $T_s = N_{disc} P_c A_{eff} R_{eff} \mu_s$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$	$\dot{\omega}_i (J_o + J_i) = T_o - \omega_i (b_i + b_o) + T_i$ $\omega_i = \omega_o$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal	Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrBase Applied base power $\omega_i T_i$ PwrFlwr Applied follower output power $\omega_o T_o$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrDampLoss Damping power loss	$-b_o \omega_o^2 - b_i \omega_i^2$
	PwrClutchSlipLoss Clutch slip power loss	$-T_k (\omega_i - \omega_o)$
PwrStored — Stored energy rate of change	PwrStoredBase Rate change in base rotational kinetic energy	$\dot{\omega}_i \omega_i J_i$
	PwrStoredFlwr Rate change in follower rotational kinetic energy	$\dot{\omega}_o \omega_o J_o$
<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 		

The equations use these variables.

ω_i	Input shaft angular speed
ω_o	Output shaft angular speed

b_i	Input shaft viscous damping
b_o	Output shaft viscous damping
J_i	Input shaft moment of inertia
J_o	Output shaft moment of inertia
T_f	Frictional torque
T_i	Net input torque
T_k	Kinetic frictional torque
T_o	Net output torque
T_s	Static frictional torque
T_{fmax}	Maximum frictional torque before slipping
P_c	Applied clutch pressure
P_{eng}	Engagement pressure
A_{eff}	Effective area
N_{disc}	Number of frictional discs
R_{eff}	Effective clutch radius
R_o	Annular disk outer radius
R_i	Annular disk inner radius
R_e	Effective tire radius while under load and for a given pressure
μ_s	Coefficient of static friction
μ_k	Coefficient of kinetic friction

Ports

Input

Press — Applied clutch pressure

scalar

Base gear input torque, P_c , in $\text{N}\cdot\text{m}^2$.

BTrq — Applied input torque

scalar

Applied input torque, T_i , typically from the engine crankshaft or dual mass flywheel damper, in $\text{N}\cdot\text{m}$.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

FTrq — Applied load torque

scalar

Applied load torque, T_o , typically from the differential or drive shaft, in $\text{N}\cdot\text{m}$.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

B – Applied drive shaft angular speed and torque

two-way connector port

Applied drive shaft angular speed, ω_i , in rad/s. Applied drive shaft torque, T_i , in N·m.**Dependencies**To create this port, for **Port Configuration**, select Two-way connection.**Output****Info – Bus signal**

bus

Bus signal containing these block calculations.

Signal		Description	Units	
Base	BTrq	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper	N·m	
	BSpd	Applied drive shaft angular speed input	rad/s	
Flwr	FTrq	Applied load torque, typically from the differential	N·m	
	FSpd	Drive shaft angular speed output	rad/s	
Cltch	CltchForce	Applied clutch force	N	
	CltchLocked	Clutch lock status	NA	
	CltchSpdRatio	Clutch speed ratio	NA	
	CltchEta	Clutch power transmission efficiency	NA	
PwrInfo	PwrTrnsfrd	PwrBase	Applied base power	W
		PwrFlwr	Applied follower output power	W
	PwrNotTrnsfrd	PwrDampLoss	Damping power loss	W
		PwrCltchSlipLoss	Clutch slip power loss	W
	PwrStored	PwrStoredBase	Rate change in base rotational kinetic energy	W
		PwrStoredFlwr	Rate change in follower rotational kinetic energy	W

BSpd – Angular speed

scalar

Applied drive shaft angular speed input, ω_i , in rad/s.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

FSpd — Angular speed

scalar

Drive shaft angular speed output, ω_o , in rad/s.

Dependencies

To create this port, for **Port Configuration**, select Simulink.

F — Output velocity and torque

two-way connector port

Output drive shaft angular speed, ω_{oi} , in rad/s. Output drive shaft torque, T_o , in N·m.

Dependencies

To create this port, for **Port Configuration**, select Two-way connection.

Parameters**Block Options****Port Configuration — Specify configuration**

Simulink (default) | Two-way connection

Specify the port configuration.

Dependencies

Specifying Simulink creates these ports:

- BSpd
- FSpd
- BTrq
- FTrq

Specifying Two-way connection creates these ports:

- B
- F

Clutch force equivalent net radius, Reff — Radius

1 (default) | scalar

Clutch force equivalent net radius, in m.

Number of disks, Ndisk — Ratio

1 (default) | scalar

Number of disks, dimensionless.

Effective applied pressure area, Aeff – Pressure area

.01 (default) | scalar

Effective applied pressure area, in m^2 .**Engagement pressure threshold, Peng – Pressure threshold**

0 (default) | scalar

Pressure to engage clutch, in Pa.

Input shaft inertia, Jin – Inertia

.1 (default) | scalar

Input shaft inertia, in $kg \cdot m^2$.**Output shaft inertia, Jout – Inertia**

.1 (default) | scalar

Output shaft inertia, in $kg \cdot m^2$.**Kinetic friction coefficient, muk – Coefficient**

.3 (default) | scalar

Kinetic friction coefficient, dimensionless.

Static friction coefficient, mus – Coefficient

.5 (default) | scalar

Static friction coefficient, dimensionless.

Input shaft viscous damping, bin – Damping

.001 (default) | scalar

Input shaft viscous damping, in $N \cdot m \cdot s/rad$.**Output shaft viscous damping, bout – Damping**

.001 (default) | scalar

Output shaft viscous damping, in $N \cdot m \cdot s/rad$.**Initial input shaft velocity, win_o – Initial velocity**

0 (default) | scalar

Input shaft initial velocity, in rad/s.

Initial output shaft velocity, wout_o – Initial velocity

0 (default) | scalar

Input shaft initial velocity, in rad/s.

Clutch actuation time constant, tauC – Constant

.01 (default) | scalar

Clutch actuation time constant, in s.

Clutch initially locked — Select to initially lock clutch

off (default) | on

Select to lock clutch initially.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

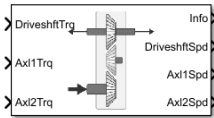
See Also

Planetary Gear | Rotational Inertia | Torque Converter | Torsional Compliance

Transfer Case

Differential as a planetary bevel gear

Library: Powertrain Blockset / Drivetrain / Final Drive Unit
Vehicle Dynamics Blockset / Powertrain / Drivetrain / Final Drive Unit



Description

The Transfer Case block implements a differential as a planetary bevel gear train. The block matches the driveshaft bevel gear to the crown (ring) bevel gear. You can specify:

- Carrier-to-driveshaft ratio
- Crown wheel location
- Viscous and damping coefficients for the axles and carrier

Use the Transfer Case block to:

- Dynamically couple the post-transmission driveshaft to the wheel axles or universal joints
- Model simplified or older drivetrains when optimal traction control does not require passive or active torque vectoring
- Model mechanical power splitting in generic gearbox and drive line scenarios

The block is suitable for use in hardware-in-the-loop (HIL) and optimization workflows. All the parameters are tunable.

Efficiency

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.

Setting	Implementation
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal	Description	Equations		
PwrInfo	PwrTrnsfrd — Power transferred between blocks	<ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	<p>PwrDriveshft: Mechanical power from driveshaft $\eta T_d \omega_d$</p> <p>PwrAx1: Mechanical power from axle 1 $\eta T_1 \omega_1$</p> <p>PwrAx2: Mechanical power from axle 2 $\eta T_2 \omega_2$</p>	
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrMechLoss	Total power loss	$\dot{W}_{loss} = -(P_t + P_d) + P_s$
		PwrDampLoss	Power loss due to damping	$P_d = -(b_1 \omega_1 + b_2 \omega_2 + b_d \omega_d)$
PwrStored — Stored energy rate of change	PwrStoredShft	Rate change of stored internal energy	$P_s = -(\omega_1 \dot{\omega}_1 J_1 + \omega_2 \dot{\omega}_2 J_2 + \omega_d \dot{\omega}_d J_d)$	

Dynamics

The Transfer Case block implements these differential equations to represent the mechanical dynamic response for the crown gear, front axle, and rear axle.

Mechanical Dynamic Response	Differential Equation
Crown Gear	$\dot{\omega}_d J_d = \eta T_d - \omega_d b_d - T_i$
Front Axle	$\dot{\omega}_1 J_1 = \eta T_1 - \omega_1 b_1 - T_{i1}$
Rear Axle	$\dot{\omega}_2 J_2 = \eta T_2 - \omega_2 b_2 - T_{i2}$

The equations use these variables.

N	Carrier-to-driveshaft gear ratio
J_d	Rotational inertia of the crown gear assembly
b_d	Crown gear linear viscous damping
ω_d	Driveshaft angular speed
η	Differential efficiency
J_1	Axle 1 rotational inertia
b_1	Axle 1 linear viscous damping
ω_1	Axle 1 speed
J_2	Axle 2 rotational inertia
b_2	Axle 2 linear viscous damping
ω_2	Axle 2 angular speed
T_d	Driveshaft torque
T_1	Axle 1 torque
T_2	Axle 2 torque
T_i	Driveshaft internal resistance torque
T_{i1}	Axle 1 internal resistance torque
T_{i2}	Axle 2 internal resistance torque

Ports

Inputs

DriveshaftTrq – Torque

scalar

Applied input torque, typically from the engine crankshaft, in N·m.

Ax11Trq – Torque

scalar

Axle 1 torque, T_1 , in N·m.

Axl2Trq – Torque

scalar

Axle 2 torque, T_2 , in N·m.

Temp – Temperature

scalar

Temperature, in K.

Dependencies

To enable this port:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Select **Input temperature**.

TrqSplitRatioConstant – Front axle torque split ratio

scalar

Front axle torque split ratio.

Dependencies

To enable this port, select **Input front axle torque split ratio, TrqSplitRatio**.

SpdLockConstant – Axle speed lock

scalar

Axle speed lock.

Dependencies

To enable this port, select **Input axle speed lock, SpdLock**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description		Units
Driveshft	DriveshftTrq		N·m
	DriveshftSpd		rad/s
Axl1	Axl1Trq		N·m
	Axl1Spd		rad/s
Axl2	Axl2Trq		N·m
	Axl2Spd		rad/s
PwrInfo	PwrTrnsfrd	PwrDriveshft	W

Signal		Description	Units	
		PwrAx11	Mechanical power from axle 1	W
		PwrAx12	Mechanical power from axle 2	W
	PwrTrnsfrd	PwrMechLoss	Total power loss	W
		PwrDampLoss	Power loss due to damping	W
	PwrStored	PwrStoredShft	Rate change of stored internal energy	W

DriveshftSpd – Angular speed

scalar

Driveshaft angular speed, ω_d , in rad/s.

Ax11Spd – Angular speed

scalar

Axle 1 angular speed, ω_1 , in rad/s.

Ax12Spd – Angular speed

scalar

Axle 2 angular speed, ω_2 , in rad/s.

Parameters

Block Options

Efficiency factors – Specify configuration

Constant (default) | Driveshaft torque, speed and temperature

To account for the block efficiency, use the **Efficiency factors** parameter. This table summarizes the block implementation for each setting.

Setting	Implementation
Constant	Constant efficiency that you can set with the Constant efficiency factor, eta parameter.

Setting	Implementation
Driveshaft torque, temperature and speed	<p>Efficiency as a function of base gear input torque, air temperature, and driveshaft speed. Use these parameters to specify the lookup table and breakpoints:</p> <ul style="list-style-type: none"> • Efficiency lookup table, eta_tbl • Efficiency torque breakpoints, Trq_bpts • Efficiency speed breakpoints, omega_bpts • Efficiency temperature breakpoints, Temp_bpts <p>For the air temperature, you can either:</p> <ul style="list-style-type: none"> • Select Input temperature to create an input port. • Set a Ambient temperature, Tamb parameter value. <p>To select the interpolation method, use the Interpolation method parameter. For more information, see “Interpolation Methods”.</p>

Interpolation method – Method

Flat | Nearest | Linear point-slope | Linear Lagrange | Cubic spline

For more information, see “Interpolation Methods”.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Input temperature – Create input port

off (default) | on

Select to create input port Temp for the temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Input front axle torque split ratio, TrqSplitRatio – Create input port

off (default) | on

Select to create input port TrqSplitRatioConstant for the front axle torque split ratio.

Input axle speed lock, SpdLock – Create input port

off (default) | on

Select to create input port SpdLockConstant for the axle speed lock.

Crown wheel (ring gear) located – Specify crown wheel connection

To the left of center-line (default) | To the right of center-line

Specify the crown wheel connection to the driveshaft.

Carrier to drive shaft ratio, Ndiff – Ratio

4 (default) | scalar

Carrier-to-driveshaft gear ratio, N , dimensionless.

Carrier inertia, Jd – Inertia

.1 (default) | scalar

Rotational inertia of the crown gear assembly, J_d , in $\text{kg}\cdot\text{m}^2$. You can include the driveshaft inertia.

Carrier damping, bd – Damping

1e-3 (default) | scalar

Crown gear linear viscous damping, b_d , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 1 inertia, Jw1 – Inertia

.1 (default) | scalar

Axle 1 rotational inertia, J_1 , in $\text{kg}\cdot\text{m}^2$.

Axle 1 damping, bw1 – Damping

1e-3 (default) | scalar

Axle 1 linear viscous damping, b_1 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 2 inertia, Jw2 – Inertia

.1 (default) | scalar

Axle 2 rotational inertia, J_2 , in $\text{kg}\cdot\text{m}^2$.

Axle 2 damping, bw2 – Damping

1e-3 (default) | scalar

Axle 2 linear viscous damping, b_2 , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Axle 1 initial velocity, omegaw1o – Angular velocity

0 (default) | scalar

Axle 1 initial velocity, ω_{o1} , in rad/s .

Axle 2 initial velocity, omegaw2o – Angular velocity

0 (default) | scalar

Axle 2 initial velocity, ω_{o2} , in rad/s .

Efficiency

Constant efficiency factor, eta – Efficiency

1 (default) | scalar

Constant efficiency, η .

Dependencies

To enable this parameter, set **Efficiency factors** to Constant.

Efficiency lookup table, eta_tbl – Lookup table

M-by-N-by-L array

Dimensionless array of values for efficiency as a function of:

- M input torques
- N input speed
- L air temperatures

Each value specifies the efficiency for a specific combination of torque, speed, and temperature. The array size must match the dimensions defined by the torque, speed, and temperature breakpoint vectors.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency torque breakpoints, Trq_bpts — Torque breakpoints

[25, 50, 75, 100, 150, 200, 250] (default) | 1-by-M vector

Vector of input torque, breakpoints for efficiency, in N·m.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency speed breakpoints, omega_bpts — Speed breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | 1-by-N vector

Vector of speed, breakpoints for efficiency, in rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Efficiency temperature breakpoints, Temp_bpts — Temperature breakpoints

[290 358] (default) | 1-by-L vector

Vector of ambient temperature breakpoints for efficiency, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Driveshaft torque, speed and temperature.

Ambient temperature, Tamb — Ambient temperature

297.15 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter:

- Set **Efficiency factors** to Driveshaft torque, speed and temperature.
- Clear **Input temperature**.

Front axle torque split ratio, TrqSplitRatio — Front axle torque split ratio

0.5 (default) | scalar

Front axle torque split ratio.

Dependencies

To enable this parameter, clear **Input front axle torque split ratio, TrqSplitRatio**.

Axle speed lock, SpdLock — Axle speed lock

0 (default) | scalar

Axle speed lock. Set this value to 0 to make the front and rear axle rotational speed not fixed. Set this value to 1 to make the front and rear axle rotational speed fixed.

Dependencies

To enable this parameter, clear **Input axle speed lock, SpdLock**.

Version History

Introduced in R2021b

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

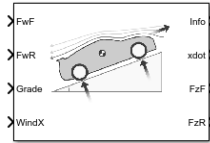
Limited Slip Differential

Vehicle Dynamics Blocks

Vehicle Body 1DOF Longitudinal

Two-axle vehicle in forward and reverse motion

Library: Powertrain Blockset / Vehicle Dynamics
Vehicle Dynamics Blockset / Vehicle Body



Description

The Vehicle Body 1DOF Longitudinal block implements a one degree-of-freedom (1DOF) rigid vehicle body with constant mass undergoing longitudinal (that is, forward and reverse) motion. Use the block:

- In powertrain and fuel economy studies to represent the vehicle inertial and drag loads when weight transfer from vertical and pitch motions are negligible.
- To determine the engine torque and power required for the vehicle to follow a specified drive cycle.

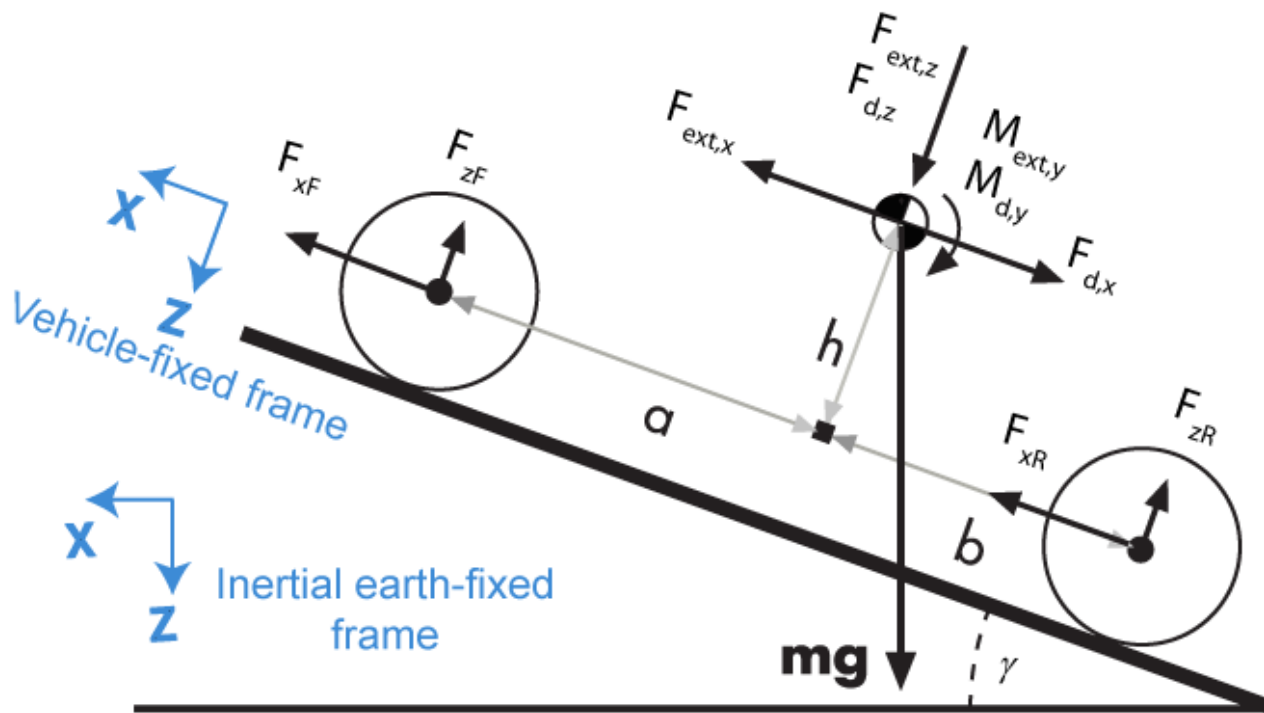
You can select block options to create input ports for external forces, moments, air temperature, and wind speed.

Block Option Setting	External Input Ports	Description
External forces	FExt	External force applied to vehicle CG in the vehicle-fixed frame.
External moments	MExt	External moment about vehicle CG in the vehicle-fixed frame.
Air temperature	AirTemp	Ambient air temperature. Consider this option if you want to vary the temperature during run-time.
Wind X,Y,Z	WindXYZ	Wind speed along earth-fixed X-, Y-, and Z-axes. If you do not select this option, the block implements input port WindX — Longitudinal wind speed along the earth-fixed X-axis.

Vehicle Body Model

The vehicle axles are parallel and form a plane. The longitudinal direction lies in this plane and is perpendicular to the axles. If the vehicle is traveling on an inclined slope, the normal direction is not parallel to gravity but is always perpendicular to the axle-longitudinal plane.

The block uses the net effect of all the forces and torques acting on it to determine the vehicle motion. The longitudinal tire forces push the vehicle forward or backward. The weight of the vehicle acts through its center of gravity (CG). The grade angle changes the direction of the resolved gravitational force acting on the vehicle CG. Similarly, the block resolves the resistive aerodynamic drag force on the vehicle CM.



The Vehicle Body 1DOF Longitudinal block implements these equations.

$$F_b = m\ddot{x}$$

$$F_b = F_{xF} + F_{xR} - F_{d,x} + F_{ext,x} - mg\sin\gamma$$

Zero normal acceleration and zero pitch torque determine the normal force on each front and rear axles.

$$F_{zF} = \frac{-M_{ext,y} - M_{d,y} + b(F_{d,z} + F_{ext,z} + mg\cos\gamma) - h(-F_{ext,x} + F_{d,x} + mg\sin\gamma + m\ddot{x})}{N_F(a + b)}$$

$$F_{zR} = \frac{M_{ext,y} + M_{d,y} + a(F_{d,z} + F_{ext,z} + mg\cos\gamma) + h(-F_{ext,x} + F_{d,x} + mg\sin\gamma + m\ddot{x})}{N_R(a + b)}$$

The wheel normal forces satisfy this equation.

$$N_FF_{zF} + N_RF_{zR} - F_{ext,z} = mg\cos\gamma$$

Wind and Drag Forces

The block subtracts the wind speeds from the vehicle velocity components to obtain a net relative airspeed. To calculate the drag force and moments acting on the vehicle, the block uses the net relative airspeed.

$$F_{d,x} = \frac{1}{2TR} C_d A_f P_{abs} \dot{x}$$

$$F_{d,z} = \frac{1}{2TR} C_l A_f P_{abs} \dot{x}$$

$$M_{d,y} = \frac{1}{2TR} C_{pm} A_f P_{abs} \dot{x} (a + b)$$

By default, to calculate the wind speed along the vehicle-fixed x-axis, the block uses the longitudinal wind speed along the earth-fixed X-axis. If you select **WindX,Y,Z**, the block uses the wind speed along the earth-fixed X-, Y-, Z-axes.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrFxExt	Externally applied force power $P_{FxExt} = F_{xExt} \dot{x}$
		PwrFwFx	Longitudinal force power applied at the front axle $P_{FwFx} = F_{wFx} \dot{x}$
		PwrFwRx	Longitudinal force power applied at the rear axle $P_{FwRx} = F_{wRx} \dot{x}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrFxDrag	Drag force power $P_d = - \frac{0.5 C_d A_f P_{abs} (\dot{x}^2 - w_x)^2}{287.058T} \dot{x}$
	PwrStored — Stored energy rate of change • Positive signals indicate an increase • Negative signals indicate a decrease	wrStoredGrvty	Rate change in gravitational potential energy $P_g = - mg \dot{Z}$
		PwrStoredxdot	Rate in change of longitudinal kinetic energy $P_{\dot{x}} = m \ddot{x} \dot{x}$

The equations use these variables.

F_{xf}, F_{xr} Longitudinal forces on each wheel at the front and rear ground contact points, respectively

F_{zf}, F_{zr}	Normal load forces on each wheel at the front and rear ground contact points, respectively
F_{wF}, F_{wR}	Longitudinal force on front and rear axles along vehicle-fixed x-axis
F_{xExt}, F_{wR}	External force along the vehicle-fixed x-axis
$F_{d,x}, F_{d,z}$	Longitudinal and normal drag force on vehicle CG
$M_{d,y}$	Torque due to drag on vehicle about the vehicle-fixed y-axis
F_d	Aerodynamic drag force
V_x	Velocity of the vehicle. When $V_x > 0$, the vehicle moves forward. When $V_x < 0$, the vehicle moves backward.
N_f, N_r	Number of wheels on front and rear axle, respectively
γ	Angle of road grade
m	Vehicle body mass
a, b	Distance of front and rear axles, respectively, from the normal projection point of vehicle CG onto the common axle plane
h	Height of vehicle CG above the axle plane
C_d	Frontal air drag coefficient
A_f	Frontal area
P_{abs}	Absolute pressure
ρ	Mass density of air
x, \dot{x}, \ddot{x}	Vehicle longitudinal position, velocity, and acceleration along the vehicle-fixed x-axis
w_x	Wind speed along the vehicle-fixed x-axis
\dot{z}	Vehicle vertical velocity along the vehicle-fixed z-axis

Limitations

The Vehicle Body 1DOF Longitudinal block lets you model only longitudinal dynamics, parallel to the ground and oriented along the direction of motion. The vehicle is assumed to be in pitch and normal equilibrium. The block does not model pitch or vertical movement. To model a vehicle with three degrees-of-freedom (DOF), use the Vehicle Body 3DOF Longitudinal.

Ports

Input

FExt — External force on vehicle CG

array

External forces applied to vehicle CG, $F_{xext}, F_{yext}, F_{zext}$, in vehicle-fixed frame, in N. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To enable this port, select **External forces**.

MExt — External moment about vehicle CG

array

External moment about vehicle CG, M_x , M_y , M_z , in the vehicle-fixed frame, in N·m. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To enable this port, select **External moments**.

FwF — Total longitudinal force on front axle

scalar

Longitudinal force on the front axle, F_{wf} , along vehicle-fixed x-axis, in N.

FwR — Total longitudinal force on rear axle

scalar

Longitudinal force on the rear axle, F_{wr} , along vehicle-fixed x-axis, in N.

Grade — Road grade angle

scalar

Road grade angle, γ , in deg.

WindX — Longitudinal wind speed

scalar

Longitudinal wind speed, W_w , along earth-fixed X-axis, in m/s.

Dependencies

To enable this port, clear **Wind X,Y,Z components**.

WindXYZ — Wind speed

array

Wind speed, W_w , W_{wy} , W_{wz} along inertial X-, Y-, and Z-axes, in m/s. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To enable this port, select **Wind X,Y,Z components**.

AirTemp — Ambient air temperature

scalar

Ambient air temperature, T_{air} , in K. Considering this option if you want to vary the temperature during run-time.

Dependencies

To enable this port, select **Air temperature**.

Output**Info — Bus signal**

bus

Bus signal containing these block values.

Signal				Description	Value	Units
InertFrm	Cg	Disp	X	Vehicle CG displacement along earth-fixed X-axis	Computed	m
			Y	Vehicle CG displacement along earth-fixed Y-axis	0	m
			Z	Vehicle CG displacement along earth-fixed Z-axis	Computed	m
		Vel	Xdot	Vehicle CG velocity along earth-fixed X-axis	Computed	m/s
			Ydot	Vehicle CG velocity along earth-fixed Y-axis	0	m/s
			Zdot	Vehicle CG velocity along earth-fixed Z-axis	Computed	m/s
		Ang	phi	Rotation of vehicle-fixed frame about the earth-fixed X-axis (roll)	0	rad
			theta	Rotation of vehicle-fixed frame about the earth-fixed Y-axis (pitch)	Computed (input - grade angle)	rad
			psi	Rotation of vehicle-fixed frame about the earth-fixed Z-axis (yaw)	0	rad
	FrntAxl	Disp	X	Front axle displacement along the earth-fixed X-axis	Computed	m
			Y	Front axle displacement along the earth-fixed Y-axis	0	m
			Z	Front axle displacement along the earth-fixed Z-axis	Computed	m
		Vel	Xdot	Front axle velocity along the earth-fixed X-axis	Computed	m/s
			Ydot	Front axle velocity along the earth-fixed Y-axis	0	m/s
			Zdot	Front axle velocity along the earth-fixed Z-axis	Computed	m/s
	RearAxl	Disp	X	Rear axle displacement along the earth-fixed X-axis	Computed	m
			Y	Rear axle displacement along the earth-fixed Y-axis	0	m
			Z	Rear axle displacement along the earth-fixed Z-axis	Computed	m

Signal			Description	Value	Units			
		Vel	Xdot	Rear axle velocity along the earth-fixed X-axis	Computed	m/s		
			Ydot	Rear axle velocity along the earth-fixed Y-axis	0	m/s		
			Zdot	Rear axle velocity along the earth-fixed Z-axis	Computed	m/s		
BdyFrm	Cg	Disp	x	Vehicle CG displacement along the vehicle-fixed x-axis	Computed	m		
			y	Vehicle CG displacement along the vehicle-fixed y-axis	0	m		
			z	Vehicle CG displacement along the vehicle-fixed z-axis	0	m		
		Vel	xdot	Vehicle CG velocity along the vehicle-fixed x-axis	Computed	m/s		
			ydot	Vehicle CG velocity along the vehicle-fixed y-axis	0	m/s		
			zdot	Vehicle CG velocity along the vehicle-fixed z-axis	0	m/s		
		AngVel	p	Vehicle angular velocity about the vehicle-fixed x-axis (roll rate)	0	rad/s		
			q	Vehicle angular velocity about the vehicle-fixed y-axis (pitch rate)	0	rad/s		
			r	Vehicle angular velocity about the vehicle-fixed z-axis (yaw rate)	0	rad/s		
		Accel	ax	Vehicle CG acceleration along the vehicle-fixed x-axis	Computed	gn		
			ay	Vehicle CG acceleration along the vehicle-fixed y-axis	0	gn		
			az	Vehicle CG acceleration along the vehicle-fixed z-axis	0	gn		
			Forces	Body	Fx	Net force on vehicle CG along the vehicle-fixed x-axis	0	N

Signal			Description	Value	Units		
			Fy	Net force on vehicle CG along the vehicle-fixed y-axis	0	N	
			Fz	Net force on vehicle CG along the vehicle-fixed z-axis	0	N	
		Ext	Fx	External force on vehicle CG along the vehicle-fixed x-axis	Computed	N	
			Fy	External force on vehicle CG along the vehicle-fixed y-axis	Computed	N	
			Fz	External force on vehicle CG along the vehicle-fixed z-axis	Computed	N	
		FrntAxl	Fx	Longitudinal force on front axle, along the vehicle-fixed x-axis	0	N	
			Fy	Lateral force on front axle, along the vehicle-fixed y-axis	0	N	
			Fz	Normal force on front axle, along the vehicle-fixed z-axis	Computed	N	
		RearAxl	Fx	Longitudinal force on rear axle, along the vehicle-fixed x-axis	0	N	
			Fy	Lateral force on rear axle, along the vehicle-fixed y-axis	0	N	
			Fz	Normal force on rear axle, along the vehicle-fixed z-axis	Computed	N	
		Tires	FrntTire	Fx	Front tire force, along the vehicle-fixed x-axis	0	N
				Fy	Front tire force, along the vehicle-fixed y-axis	0	N
				Fz	Front tire force, along the vehicle-fixed z-axis	Computed	N
			RearTire	Fx	Rear tire force, along the vehicle-fixed x-axis	0	N
Fy	Rear tire force, along the vehicle-fixed y-axis			0	N		

Signal				Description	Value	Units		
			F _z	Rear tire force, along the vehicle-fixed z-axis	Computed	N		
		Drag	F _x	Drag force on vehicle CG along the vehicle-fixed x-axis	Computed	N		
			F _y	Drag force on vehicle CG along the vehicle-fixed y-axis	Computed	N		
			F _z	Drag force on vehicle CG along the vehicle-fixed z-axis	Computed	N		
		Grvty	F _x	Gravity force on vehicle CG along the vehicle-fixed x-axis	Computed	N		
			F _y	Gravity force on vehicle CG along the vehicle-fixed y-axis	0	N		
			F _z	Gravity force on vehicle CG along the vehicle-fixed z-axis	Computed	N		
	Moments	Body	M _x	Net moment on vehicle CG about the vehicle-fixed x-axis	0	N·m		
				M _y	Net moment on vehicle CG about the vehicle-fixed y-axis	0	N·m	
				M _z	Net moment on vehicle CG about the vehicle-fixed z-axis	0	N·m	
			Drag	M _x	Drag moment on vehicle CG about the vehicle-fixed x-axis	Computed	N·m	
					M _y	Drag moment on vehicle CG about the vehicle-fixed y-axis	Computed	N·m
					M _z	Drag moment on vehicle CG about the vehicle-fixed z-axis	Computed	N·m
			Ext	F _x	External moment on vehicle CG about the vehicle-fixed x-axis	Computed	N·m	
					F _y	External moment on vehicle CG about the vehicle-fixed y-axis	Computed	N·m

Signal			Description	Value	Units	
		Fz	External moment on vehicle CG about the vehicle-fixed z-axis	Computed	N·m	
FrntAxl	Disp	x	Front axle displacement along the vehicle-fixed x-axis	Computed	m	
		y	Front axle displacement along the vehicle-fixed y-axis	0	m	
		z	Front axle displacement along the vehicle-fixed z-axis	Computed	m	
	Vel	xdot	Front axle velocity along the vehicle-fixed x-axis	Computed	m/s	
		ydot	Front axle velocity along the vehicle-fixed y-axis	0	m/s	
		zdot	Front axle velocity along the vehicle-fixed z-axis	Computed	m/s	
	Steer	WhlAngFL	Front left wheel steering angle	Computed	rad	
		WhlAngFR	Front right wheel steering angle	Computed	rad	
	RearAxl	Disp	x	Rear axle displacement along the vehicle-fixed x-axis	Computed	m
			y	Rear axle displacement along the vehicle-fixed y-axis	0	m
			z	Rear axle displacement along the vehicle-fixed z-axis	Computed	m
		Vel	xdot	Rear axle velocity along the vehicle-fixed x-axis	Computed	m/s
ydot			Rear axle velocity along the vehicle-fixed y-axis	0	m/s	
zdot			Rear axle velocity along the vehicle-fixed z-axis	Computed	m/s	
Steer		WhlAngRL	Rear left wheel steering angle	Computed	rad	
		WhlAngRR	Rear right wheel steering angle	Computed	rad	
Pwr		PwrExt		Applied external power	Computed	W
		Drag		Power loss due to drag	Computed	W

Signal			Description	Value	Units
PwrInfo	PwrTrnsfrd	PwrFxExt	Externally applied force power	Computed	W
		PwrFwFx	Longitudinal force power applied at the front axle	Computed	W
		PwrFwRx	Longitudinal force power applied at the rear axle	Computed	W
	PwrNotTrnsfrd	PwrFxDrag	Drag force power	Computed	W
	PwrStored	wrStoredGrvty	Rate change in gravitational potential energy	Computed	W
		PwrStoredxdot	Rate in change of longitudinal kinetic energy	Computed	W

xdot – Vehicle body longitudinal velocity

scalar

Vehicle body longitudinal velocity along the vehicle-fixed reference frame x-axis, in m/s.

FzF – Front axle normal force

scalar

Normal load force on the front axle, F_{zf} , along vehicle-fixed z-axis, in N.

FzR – Rear axle normal force

scalar

Normal force on rear axle, F_{zr} , along the vehicle-fixed z-axis, in N.

Parameters

Options

External forces – FExt input port

off (default) | on

Specify to create input port FExt.

External moments – MExt input port

off (default) | on

Specify to create input port MExt.

Air temperature – AirTemp input port

off (default) | on

Specify to create input port AirTemp.

Wind X,Y,Z components – WindXYZ input port

off (default) | on

Specify to create input port WindXYZ.

Longitudinal

Number of wheels on front axle, NF – Front wheel count

2 (default) | scalar

Number of wheels on front axle, N_F . The value is dimensionless.

Number of wheels on rear axle, NR – Rear wheel count

2 (default) | scalar

Number of wheels on rear axle, N_R . The value is dimensionless.

Mass, m – Vehicle mass

1500 (default) | scalar

Vehicle mass, M , in kg.

Horizontal distance from CG to front axle, a – Front axle distance

1.4 (default) | scalar

Horizontal distance a from the vehicle CG to the front wheel axle, in m.

Horizontal distance from CG to rear axle, b – Rear axle distance

1.8 (default) | scalar

Horizontal distance b from the vehicle CG to the rear wheel axle, in m.

CG height above axles, h – Height

.35 (default) | scalar

Height of vehicle CG above the ground, h , in m.

Longitudinal drag coefficient, Cd – Drag

.3 (default) | scalar

Air drag coefficient, C_d . The value is dimensionless.

Longitudinal lift coefficient, Cl – Lift

0 (default) | scalar

Air lift coefficient, C_l . The value is dimensionless.

Longitudinal drag pitch moment, Cpm – Pitch drag

0 (default) | scalar

Pitch drag moment coefficient, C_{pm} . The value is dimensionless.

Frontal area, Af – Area

4 (default) | scalar

Effective vehicle cross-sectional area, A , to calculate the aerodynamic drag force on the vehicle, in m^2 .

Initial position, x_o – Position

0 (default) | scalar

Vehicle body longitudinal initial position along the vehicle-fixed x-axis, x_0 , in m.

Initial velocity, \dot{x}_0 – Velocity

0 (default) | scalar

Vehicle body longitudinal initial velocity along the vehicle-fixed x-axis, \dot{x}_0 , in m/s.

Environment

Absolute air pressure, P_{abs} – Pressure

101325 (default) | scalar

Environmental air absolute pressure, P_{abs} , in Pa.

Air temperature, T – Ambient air temperature

273 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter, clear **Air temperature**.

Gravitational acceleration, g – Gravity

9.81 (default) | scalar

Gravitational acceleration, g , in m/s^2 .

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

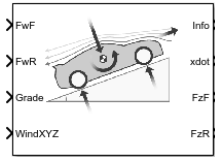
See Also

Vehicle Body 3DOF Longitudinal | Vehicle Body Total Road Load

Vehicle Body 3DOF Longitudinal

3DOF rigid vehicle body to calculate longitudinal, vertical, and pitch motion

Library: Powertrain Blockset / Vehicle Dynamics
Vehicle Dynamics Blockset / Vehicle Body



Description

The Vehicle Body 3DOF Longitudinal block implements a three degrees-of-freedom (3DOF) rigid vehicle body model with configurable axle stiffness to calculate longitudinal, vertical, and pitch motion. The block accounts for body mass, aerodynamic drag, road incline, and weight distribution between the axles due to acceleration and the road profile.

You can specify the type of axle attachment to the vehicle:

- Grade angle — Vertical axle displacement from road surface to axles remains constant. The block uses tabular stiffness and damping parameters to model the suspension forces acting between the vehicle body and axles.
- Axle displacement — Axles have input-provided vertical displacement and velocity with respect to the road grade. The block uses tabular stiffness and damping parameters to model the suspension forces acting between the vehicle body and axle.
- External suspension — Axles have externally applied forces for coupling the vehicle body to custom suspension models.

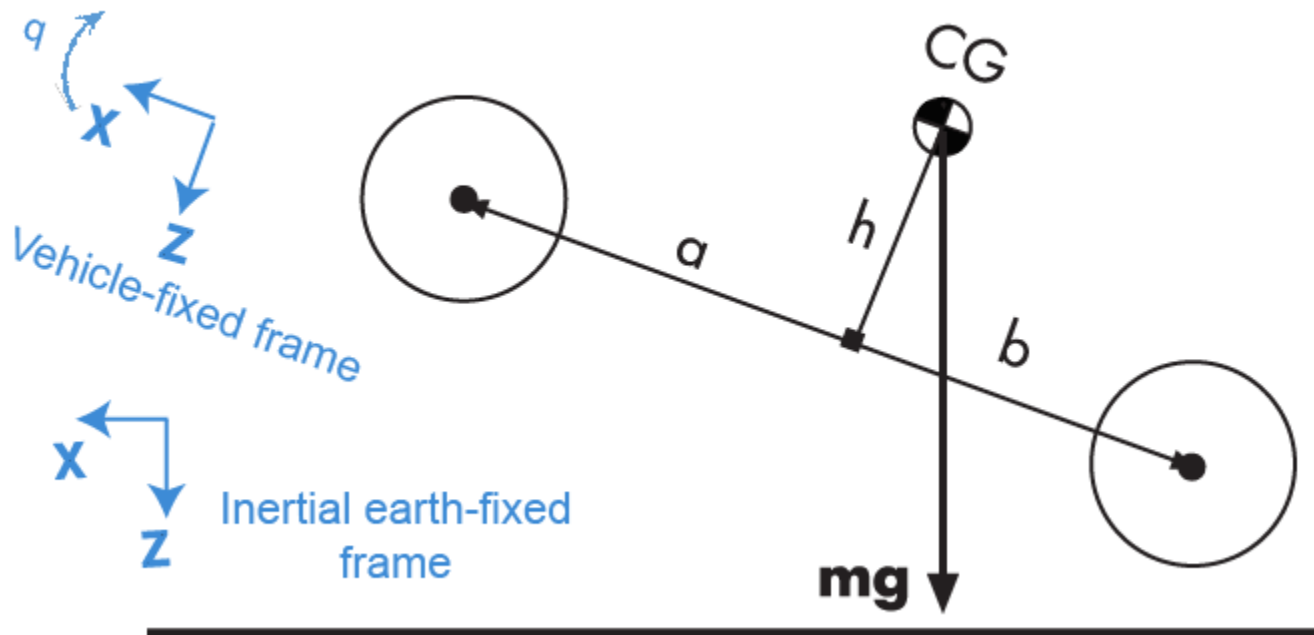
If the weight transfer from vertical and pitch motions are not negligible, consider using this block to represent vehicle motion in powertrain and fuel economy studies. For example, in studies with heavy braking or acceleration or road profiles that contain larger vertical changes.

The block uses rigid-body vehicle motion, suspension system forces, and wind and drag forces to calculate the normal forces on the front and rear axles. The block resolves the force components and moments on the rigid vehicle body frame:

$$F_x = F_{wF} + F_{wR} - F_{d,x} - F_{sx,F} - F_{sx,R} + F_{g,x}$$

$$F_z = F_{d,z} - F_{sz,F} - F_{sz,R} + F_{g,z}$$

$$M_y = aF_{sz,F} - bF_{sz,R} + h(F_{wF} + F_{wR} + F_{sx,F} + F_{sx,R}) - M_{d,y}$$



Rigid-Body Vehicle Motion

The vehicle axles are parallel and form a plane. The longitudinal direction lies in this plane and is perpendicular to the axles. If the vehicle is traveling on an inclined slope, the normal direction is not parallel to gravity but is always perpendicular to the axle-longitudinal plane.

The block uses the net effect of all the forces and torques acting on it to determine the vehicle motion. The longitudinal tire forces push the vehicle forward or backward. The weight of the vehicle acts through its center of gravity (CG). Depending on the inclined angle, the weight pulls the vehicle to the ground and either forward or backward. Whether the vehicle travels forward or backward, aerodynamic drag slows it down. For simplicity, the drag is assumed to act through the CG.

The Vehicle Body 3DOF Longitudinal implements these equations.

$$\ddot{x} = \frac{F_x}{m} - qz$$

$$\ddot{z} = \frac{F_z}{m} - qx$$

$$\dot{q} = \frac{M_y}{I_{yy}}$$

$$\dot{\theta} = q$$

Suspension System Forces

If you configure the block with the **Ground interaction type** parameter `Grade angle` or `Axle displacement, velocity`, the block uses nonlinear stiffness and damping parameters to model the suspension system.

The front and rear axle suspension forces are given by:

$$F_{S_F} = N_F[Fk_F + Fb_F]$$

$$F_{S_R} = N_R[Fk_R + Fb_R]$$

The block uses lookup tables to implement the front and rear suspension stiffness. To account for kinematic and material nonlinearities, including collisions with end-stops, the tables are functions of the stroke.

$$Fk_F = f(dZ_F)$$

$$Fk_R = f(dZ_R)$$

The block uses lookup tables to implement the front and rear suspension damping. To account for nonlinearities, compression, and rebound, the tables are functions of the stroke rate.

$$Fb_F = f(d\dot{Z}_F)$$

$$Fb_R = f(d\dot{Z}_R)$$

The stroke is the difference in the vehicle vertical and axle positions. The stroke rate is the difference in the vertical and axle velocities.

$$dZ_F = Z_F - \bar{Z}_F$$

$$dZ_R = Z_R - \bar{Z}_R$$

$$d\dot{Z}_F = \dot{Z}_F - \dot{\bar{Z}}_F$$

$$d\dot{Z}_R = \dot{Z}_R - \dot{\bar{Z}}_R$$

When the **Ground interaction type** parameter is `Grade angle`, the axle vertical positions (\bar{Z}_F, \bar{Z}_R) and velocities ($\dot{\bar{Z}}_F, \dot{\bar{Z}}_R$) are set to θ .

Wind and Drag Forces

The block subtracts the wind speeds from the vehicle velocity components to obtain a net relative airspeed. To calculate the drag force and moments acting on the vehicle, the block uses the net relative airspeed:

$$F_{d,x} = \frac{1}{2TR} C_d A_f P_{abs}(\dot{x})$$

$$F_{d,z} = \frac{1}{2TR} C_l A_f P_{abs}(\dot{x})$$

$$M_{d,y} = \frac{1}{2TR} C_{pm} A_f P_{abs}(\dot{x})(a + b)$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrFxExt	Externally applied longitudinal force power	$P_{FxExt} = F_{xExt}\dot{x}$
		PwrFzExt	Externally applied longitudinal force power	$P_{FzExt} = F_{zExt}\dot{z}$
		PwrMyExt	Externally applied pitch moment power	$P_{MzExt} = M_{zExt}\dot{\theta}$
		PwrFwFx	Longitudinal force applied at the front axle	$P_{FwFx} = F_{wFx}\dot{x}$
		PwrFwRx	Longitudinal force applied at the rear axle	$P_{FwRx} = F_{wRx}\dot{x}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrFsF	Internal power transferred between suspension and vehicle body at the front axle	$P_{Fs,F} = -P_{FwFx} + P_{FsbF} + P_{Fsk,F} + F_{xF}\dot{x}_F + F_{zF}\dot{z}_F$
		PwrFsR	Internal power transferred between suspension and vehicle body at the rear axle	$P_{Fs,R} = -P_{FwRx} + P_{Fsb,R} + P_{Fsk,R} + F_{xF}\dot{x}_F + F_{zF}\dot{z}_F$
		PwrFxDrag	Longitudinal drag force power	$P_{d,x} = F_{d,x}\dot{x}$
		PwrFzDrag	Vertical drag force power	$P_{d,z} = F_{d,z}\dot{z}$
		PwrMyDrag	Drag pitch moment power	$P_{d,My} = M_{d,y}\dot{\theta}$
		PwrFsb	Total suspension damping power	$P_{Fsb} = \sum_{i=F,R} F_{sb,i}\dot{z}_i$
		PwrStored — Stored energy rate of change	PwrStoredGrvty	Rate change in gravitational potential energy
	PwrStoredxdot		Rate of change of longitudinal kinetic energy	$P_{\dot{x}} = m\dot{x}\dot{x}$
	PwrStoredzdot		Rate of change of longitudinal kinetic energy	$P_{\dot{z}} = m\dot{z}\dot{z}$

Bus Signal		Description	Equations
	PwrStoredq	Rate of change of rotational pitch kinetic energy	$P_{\dot{\theta}} = I_{yy}\ddot{\theta}$
	PwrStoredFsFzSprng	Stored spring energy from front suspension	$P_{FskF} = F_{sk,F}\dot{z}_F$
	PwrStoredFsRzSprng	Stored spring energy from rear suspension	$P_{FskR} = F_{sk,R}\dot{z}_R$

The equations use these variables.

F_x	Longitudinal force on vehicle
F_z	Normal force on vehicle
M_y	Torque on vehicle about the vehicle-fixed y-axis
F_{wF}, F_{wR}	Longitudinal force on front and rear axles along vehicle-fixed x-axis
$F_{d,x}, F_{d,z}$	Longitudinal and normal drag force on vehicle CG
$F_{sx,F}, F_{sx,R}$	Longitudinal suspension force on front and rear axles
$F_{sz,F}, F_{sz,R}$	Normal suspension force on front and rear axles
$F_{g,x}, F_{g,z}$	Longitudinal and normal gravitational force on vehicle along the vehicle-fixed frame
$M_{d,y}$	Torque due to drag on vehicle about the vehicle-fixed y-axis
a, b	Distance of front and rear axles, respectively, from the normal projection point of vehicle CG onto the common axle plane
h	Height of vehicle CG above the axle plane along vehicle-fixed z-axis
F_{sF}, F_{sR}	Front and rear axle suspension force along vehicle-fixed z-axis
Z_{wF}, Z_{wR}	Front and rear vehicle normal position along earth-fixed z-axis
θ	Vehicle pitch angle about the vehicle-fixed y-axis
m	Vehicle body mass
N_F, N_R	Number of front and rear wheels
I_{yy}	Vehicle body moment of inertia about the vehicle-fixed y-axis
x, \dot{x}, \ddot{x}	Vehicle longitudinal position, velocity, and acceleration along the vehicle-fixed x-axis
z, \dot{z}, \ddot{z}	Vehicle normal position, velocity, and acceleration along the vehicle-fixed z-axis
Fk_F, Fk_R	Front and rear wheel suspension stiffness force along vehicle-fixed z-axis
Fb_F, Fb_R	Front and rear wheel suspension damping force along vehicle-fixed z-axis
Z_F, Z_R	Front and rear vehicle vertical position along earth-fixed Z-axis
\dot{Z}_F, \dot{Z}_R	Front and rear vehicle vertical velocity along vehicle-fixed z-axis
\bar{Z}_F, \bar{Z}_R	Front and rear wheel axle vertical position along vehicle-fixed z-axis
$\dot{\bar{Z}}_F, \dot{\bar{Z}}_R$	Front and rear wheel axle vertical velocity along earth-fixed z-axis

dZ_F, dZ_R	Front and rear axle suspension deflection along vehicle-fixed z -axis
$d\dot{Z}_F, d\dot{Z}_R$	Front and rear axle suspension deflection rate along vehicle-fixed z -axis
C_d	Frontal air drag coefficient acting along the vehicle-fixed x -axis
C_l	Lateral air drag coefficient acting along the vehicle-fixed z -axis
C_{pm}	Air drag pitch moment acting about the vehicle-fixed y -axis
A_f	Frontal area
P_{abs}	Environmental absolute pressure
R	Atmospheric specific gas constant
T	Environmental air temperature
w_x	Wind speed along the vehicle-fixed x -axis

Ports

Input

FExt — External force on vehicle CG

array

External forces applied to vehicle CG, $F_{x_{ext}}, F_{y_{ext}}, F_{z_{ext}}$, in vehicle-fixed frame, in N. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To enable this port, select **External forces**.

MExt — External moment about vehicle CG

array

External moment about vehicle CG, M_x, M_y, M_z , in the vehicle-fixed frame, in N·m. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To enable this port, select **External moments**.

FwF — Total longitudinal force on the front axle

scalar

Longitudinal force on the front axle, F_{wF} , along vehicle-fixed x -axis, in N.

FwR — Total longitudinal force on the rear axle

scalar

Longitudinal force on the rear axle, F_{wR} , along vehicle-fixed x -axis, in N.

Grade — Road grade angle

scalar

Road grade angle, γ , in deg.

FsF — Suspension force on front axle per wheel

vector

Suspension force on front axle, F_{s_F} , along the vehicle-fixed z -axis, in N.

Dependencies

To enable this port, for the **Ground interaction type** parameter, select External suspension.

FsR — Suspension force on rear axle per wheel

vector

Suspension force on rear axle, F_{s_R} , along the vehicle-fixed z -axis, in N.

Dependencies

To enable this port, for the **Ground interaction type** parameter, select External suspension.

WindXYZ — Wind speed

array

Wind speed, W_x , W_y , W_z along earth-fixed X -, Y -, and Z -axes, in m/s. Signal vector dimensions are $[1 \times 3]$ or $[3 \times 1]$.

AirTemp — Ambient air temperature

scalar

Ambient air temperature, T_{air} , in K. Considering this option if you want to vary the temperature during run-time.

Dependencies

To enable this port, select **Air temperature**.

zF,R — Forward and rear axle positions

vector

Forward and rear axle positions along the vehicle-fixed z -axis, \bar{z}_F, \bar{z}_R , in m.

Dependencies

To enable this port, for the **Ground interaction type** parameter, select Axle displacement, velocity.

zdotF,R — Forward and rear axle velocities

vector

Forward and rear axle velocities along the vehicle-fixed z -axis, $\dot{\bar{z}}_F, \dot{\bar{z}}_R$, in m/s.

Dependencies

To enable this port, for the **Ground interaction type** parameter, select Axle displacement, velocity.

Output

Info — Bus signal

bus

Bus signal containing these block values.

Signal				Description	Value	Units
InertFrm	Cg	Disp	X	Vehicle CG displacement along earth-fixed X-axis	Computed	m
			Y	Vehicle CG displacement along earth-fixed Y-axis	0	m
			Z	Vehicle CG displacement along earth-fixed Z-axis	Computed	m
		Vel	Xdot	Vehicle CG velocity along earth-fixed X-axis	Computed	m/s
			Ydot	Vehicle CG velocity along earth-fixed Y-axis	0	m/s
			Zdot	Vehicle CG velocity along earth-fixed Z-axis	Computed	m/s
		Ang	phi	Rotation of vehicle-fixed frame about the earth-fixed X-axis (roll)	0	rad
			theta	Rotation of vehicle-fixed frame about the earth-fixed Y-axis (pitch)	Computed	rad
			psi	Rotation of vehicle-fixed frame about the earth-fixed Z-axis (yaw)	0	rad
	FrntAxl	Disp	X	Front axle displacement along the earth-fixed X-axis	Computed	m
			Y	Front axle displacement along the earth-fixed Y-axis	0	m
			Z	Front axle displacement along the earth-fixed Z-axis	Computed	m
		Vel	Xdot	Front axle velocity along the earth-fixed X-axis	Computed	m/s
			Ydot	Front axle velocity along the earth-fixed Y-axis	0	m/s
			Zdot	Front axle velocity along the earth-fixed Z-axis	Computed	m/s
	RearAxl	Disp	X	Rear axle displacement along the earth-fixed X-axis	Computed	m
			Y	Rear axle displacement along the earth-fixed Y-axis	0	m
			Z	Rear axle displacement along the earth-fixed Z-axis	Computed	m
		Vel	Xdot	Rear axle velocity along the earth-fixed X-axis	Computed	m/s
			Ydot	Rear axle velocity along the earth-fixed Y-axis	0	m/s

Signal				Description	Value	Units	
			Zdot	Rear axle velocity along the earth-fixed Z-axis	Computed	m/s	
BdyFrm	Cg	Disp	x	Vehicle CG displacement along the vehicle-fixed x-axis	Computed	m	
			y	Vehicle CG displacement along the vehicle-fixed y-axis	0	m	
			z	Vehicle CG displacement along the vehicle-fixed z-axis	Computed	m	
		Vel	xdot	Vehicle CG velocity along the vehicle-fixed x-axis	Computed	m/s	
			ydot	Vehicle CG velocity along the vehicle-fixed y-axis	0	m/s	
			zdot	Vehicle CG velocity along the vehicle-fixed z-axis	Computed	m/s	
		AngVel	p	Vehicle angular velocity about the vehicle-fixed x-axis (roll rate)	0	rad/s	
			q	Vehicle angular velocity about the vehicle-fixed y-axis (pitch rate)	Computed	rad/s	
			r	Vehicle angular velocity about the vehicle-fixed z-axis (yaw rate)	0	rad/s	
		Accel	ax	Vehicle CG acceleration along the vehicle-fixed x-axis	Computed	gn	
			ay	Vehicle CG acceleration along the vehicle-fixed y-axis	0	gn	
			az	Vehicle CG acceleration along the vehicle-fixed z-axis	Computed	gn	
		Forces	Body	Fx	Net force on vehicle CG along the vehicle-fixed x-axis	Computed	N
				Fy	Net force on vehicle CG along the vehicle-fixed y-axis	0	N
				Fz	Net force on vehicle CG along the vehicle-fixed z-axis	Computed	N

Signal		Description		Value	Units		
	Ext	Fx	External force on vehicle CG along the vehicle-fixed x-axis	Computed	N		
			Fy	External force on vehicle CG along the vehicle-fixed y-axis	Computed	N	
				Fz	External force on vehicle CG along the vehicle-fixed z-axis	Computed	N
		FrntAxl			Fx	Longitudinal force on front axle, along the vehicle-fixed x-axis	Computed
			Fy			Lateral force on front axle, along the vehicle-fixed y-axis	0
				Fz		Normal force on front axle, along the vehicle-fixed z-axis	Computed
		RearAxl			Fx	Longitudinal force on rear axle, along the vehicle-fixed x-axis	Computed
			Fy			Lateral force on rear axle, along the vehicle-fixed y-axis	0
				Fz		Normal force on rear axle, along the vehicle-fixed z-axis	Computed
	Tires	FrntTire			Fx	Front tire force, along the vehicle-fixed x-axis	0
			Fy		Front tire force, along the vehicle-fixed y-axis	0	N
			Fz	Front tire force, along the vehicle-fixed z-axis	Computed	N	
		RearTire	Fx	Rear tire force, along the vehicle-fixed x-axis	0	N	
			Fy	Rear tire force, along the vehicle-fixed y-axis	0	N	
			Fz	Rear tire force, along the vehicle-fixed z-axis	Computed	N	
	Drag	Fx	Drag force on vehicle CG along the vehicle-fixed x-axis	Computed	N		

Signal			Description	Value	Units	
		Grvty	Fy	Drag force on vehicle CG along the vehicle-fixed y-axis	Computed	N
			Fz	Drag force on vehicle CG along the vehicle-fixed z-axis	Computed	N
			Fx	Gravity force on vehicle CG along the vehicle-fixed x-axis	Computed	N
			Fy	Gravity force on vehicle CG along the vehicle-fixed y-axis	0	N
			Fz	Gravity force on vehicle CG along the vehicle-fixed z-axis	Computed	N
	Moments	Body	Mx	Body moment on vehicle CG about the vehicle-fixed x-axis	0	N·m
			My	Body moment on vehicle CG about the vehicle-fixed y-axis	Computed	N·m
			Mz	Body moment on vehicle CG about the vehicle-fixed z-axis	0	N·m
		Drag	Mx	Drag moment on vehicle CG about the vehicle-fixed x-axis	0	N·m
			My	Drag moment on vehicle CG about the vehicle-fixed y-axis	Computed	N·m
			Mz	Drag moment on vehicle CG about the vehicle-fixed z-axis	0	N·m
		Ext	Fx	External moment on vehicle CG about the vehicle-fixed x-axis	Computed	N·m
			Fy	External moment on vehicle CG about the vehicle-fixed y-axis	Computed	N·m
			Fz	External moment on vehicle CG about the vehicle-fixed z-axis	Computed	N·m
	FrntAxl	Disp	x	Front axle displacement along the vehicle-fixed x-axis	Computed	m

Signal			Description	Value	Units		
			y	Front axle displacement along the vehicle-fixed y-axis	0	m	
			z	Front axle displacement along the vehicle-fixed z-axis	Computed	m	
		Vel	xdot	Front axle velocity along the vehicle-fixed x-axis	Computed	m/s	
			ydot	Front axle velocity along the vehicle-fixed y-axis	0	m/s	
			zdot	Front axle velocity along the vehicle-fixed z-axis	Computed	m/s	
		Steer	WhlAngFL	Front left wheel steering angle	Computed	rad	
			WhlAngFR	Front right wheel steering angle	Computed	rad	
		RearAxl	Disp	x	Rear axle displacement along the vehicle-fixed x-axis	Computed	m
				y	Rear axle displacement along the vehicle-fixed y-axis	0	m
				z	Rear axle displacement along the vehicle-fixed z-axis	Computed	m
	Vel		xdot	Rear axle velocity along the vehicle-fixed x-axis	Computed	m/s	
			ydot	Rear axle velocity along the vehicle-fixed y-axis	0	m/s	
			zdot	Rear axle velocity along the vehicle-fixed z-axis	Computed	m/s	
	Steer		WhlAngRL	Rear left wheel steering angle	Computed	rad	
			WhlAngRR	Rear right wheel steering angle	Computed	rad	
	Pwr		PwrExt	Applied external power	Computed	W	
			Drag	Power loss due to drag	Computed	W	
	PwrInfo	PwrTrns frd	PwrFxExt	Externally applied longitudinal force power	Computed	W	
			PwrFzExt	Externally applied longitudinal force power	Computed	W	
			PwrMyExt	Externally applied pitch moment power	Computed	W	

Signal		Description	Value	Units	
		PwrFwFx	Longitudinal force applied at the front axle	Computed	W
		PwrFwRx	Longitudinal force applied at the rear axle	Computed	W
	PwrNotT rnsfrd	PwrFsF	Internal power transferred between suspension and vehicle body at the front axle	Computed	W
		PwrFsR	Internal power transferred between suspension and vehicle body at the rear axle	Computed	W
		PwrFxDrag	Longitudinal drag force power	Computed	W
		PwrFzDrag	Vertical drag force power	Computed	W
		PwrMyDrag	Drag pitch moment power	Computed	W
		PwrFsb	Total suspension damping power	Computed	W
		PwrStor ed	PwrStoredGrvty	Rate change in gravitational potential energy	Computed
	PwrStoredxdot		Rate of change of longitudinal kinetic energy	Computed	W
	PwrStoredzdot		Rate of change of longitudinal kinetic energy	Computed	W
	PwrStoredq		Rate of change of rotational pitch kinetic energy	Computed	W
	PwrStoredFsFzSprng		Stored spring energy from front suspension	Computed	W
	PwrStoredFsRzSprng		Stored spring energy from rear suspension	Computed	W

xdot – Vehicle longitudinal velocity

scalar

Vehicle CG velocity along the vehicle-fixed x -axis, in m/s.**FzF – Front axle normal force**

scalar

Normal force on front axle, Fz_F , along the vehicle-fixed z -axis, in N.**FzR – Rear axle normal force**

scalar

Normal force on rear axle, Fz_R , along the vehicle-fixed z -axis, in N.

Parameters

Options

External forces – FExt input port

off (default) | on

Specify to create input port FExt.

External moments – MExt input port

off (default) | on

Specify to create input port MExt.

Air temperature – AirTemp input port

off (default) | on

Specify to create input port AirTemp.

Longitudinal

Number of wheels on front axle, NF – Front wheel count

2 (default) | scalar

Number of wheels on front axle, N_F . The value is dimensionless.**Number of wheels on rear axle, NR – Rear wheel count**

2 (default) | scalar

Number of wheels on rear axle, N_R . The value is dimensionless.**Mass, m – Vehicle mass**

1200 (default) | scalar

Vehicle mass, m , in kg.**Horizontal distance from CG to front axle, a – Front axle distance**

1.4 (default) | scalar

Horizontal distance a from the vehicle CG to the front wheel axle, in m.**Horizontal distance from CG to rear axle, b – Rear axle distance**

1.8 (default) | scalar

Horizontal distance b from the vehicle CG to the rear wheel axle, in m.**CG height above axles, h – Height**

0.35 (default) | scalar

Height of vehicle CG above the axles, h , in m.**Longitudinal drag coefficient, Cd – Drag**

.3 (default) | scalar

Air drag coefficient, C_d . The value is dimensionless.

Frontal area, A_f – Area

2 (default) | scalar

Effective vehicle cross-sectional area, A_f to calculate the aerodynamic drag force on the vehicle, in m^2 .

Initial position, x_o – Position

0 (default) | scalar

Vehicle body longitudinal initial position along earth-fixed x-axis, x_o , in m.

Initial velocity, \dot{x}_o – Velocity

0 (default) | scalar

Vehicle body longitudinal initial velocity along earth-fixed x-axis, \dot{x}_o , in m/s.

Vertical**Longitudinal lift coefficient, C_l – Lift**

.1 (default) | scalar

Lift coefficient, C_l . The value is dimensionless.

Initial vertical position, z_o – Position

-.35 (default) | scalar

Initial vertical CG position, z_o , along the vehicle-fixed z-axis, in m.

Initial vertical velocity, \dot{z}_o – Velocity

0 (default) | scalar

Initial vertical CG velocity, \dot{z}_o , along the vehicle-fixed z-axis, in m.

Pitch**Inertia, I_{yy} – About body y-axis**

3500 (default) | scalar

Vehicle body moment of inertia about body z-axis.

Longitudinal drag pitch moment, C_{pm} – Drag coefficient

.1 (default) | scalar

Pitch drag moment coefficient. The value is dimensionless.

Initial pitch angle, θ_o – Pitch

0 (default) | scalar

Initial pitch angle about body z-axis, in rad.

Initial angular velocity, q_o – Pitch velocity

0 (default) | scalar

Initial vehicle body angular velocity about body z-axis, in rad/s.

Suspension**Front axle stiffness force data, FskF — Force**

[-50, -1, 0, 2, 3, 52].*1.5e4 (default) | vector

Front axle stiffness force data, Fk_F , in N.**Dependencies**

To enable this parameter, for the **Ground interaction type** parameter, select **Grade angle** or **Axle displacement, velocity**.

Front axle displacement data, dzsF — Displacement

[-5e-3, -1e-4, 0, .2, .2001, .2051] (default) | vector

Front axle displacement data, in m.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select **Grade angle** or **Axle displacement, velocity**.

Front axle damping force data, FsbF — Damping force

[-10000 -100 -10 0 10 100 10000] (default) | vector

Front axle damping force, in N.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select **Grade angle** or **Axle displacement, velocity**.

Front axle velocity data, dzdotsF — Velocity

[-10 -1 -.1 0 .1 1 10] (default) | vector

Front axle velocity data, in m/s.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select **Grade angle** or **Axle displacement, velocity**.

Rear axle stiffness force data, FskR — Force

[-50, -1, 0, 2, 3, 52].*1e4 (default) | vector

Rear axle stiffness force data, in N.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select **Grade angle** or **Axle displacement, velocity**.

Rear axle displacement data, dzsR — Displacement

[-5e-3, -1e-4, 0, .2, .2001, .2051] (default) | vector

Rear axle displacement data, in m.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select `Grade angle` or `Axle displacement, velocity`.

Rear axle damping force data, FsbR — Damping force

`[-10000 -100 -10 0 10 100 10000]` (default) | `vector`

Rear axle damping force, in N.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select `Grade angle` or `Axle displacement, velocity`.

Rear axle velocity data, dzdotsR — Velocity

`[-10 -1 -.1 0 .1 1 10]` (default) | `vector`

Rear axle velocity data, in m/s.

Dependencies

To enable this parameter, for the **Ground interaction type** parameter, select `Grade angle` or `Axle displacement, velocity`.

Environment**Absolute air pressure, Pabs — Pressure**

`101325` (default) | `scalar`

Environmental air absolute pressure, P_{abs} , in Pa.

Air temperature, Tair — Ambient air temperature

`273` (default) | `scalar`

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter, clear **Air temperature**.

Gravitational acceleration, g — Gravity

`9.81` (default)

Gravitational acceleration, g , in m/s^2 .

Version History

Introduced in R2017a

References

[1] Gillespie, Thomas. *Fundamentals of Vehicle Dynamics*. Warrendale, PA: Society of Automotive Engineers, 1992.

[2] Vehicle Dynamics Standards Committee. *Vehicle Dynamics Terminology*. SAE J670. Warrendale, PA: Society of Automotive Engineers, 2008.

[3] Technical Committee. *Road vehicles — Vehicle dynamics and road-holding ability — Vocabulary*. ISO 8855:2011. Geneva, Switzerland: International Organization for Standardization, 2011.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

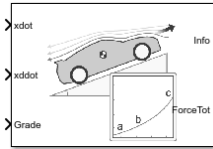
See Also

Vehicle Body 1DOF Longitudinal | Vehicle Body Total Road Load

Vehicle Body Total Road Load

Vehicle motion using coast-down testing coefficients

Library: Powertrain Blockset / Vehicle Dynamics
Vehicle Dynamics Blockset / Vehicle Body



Description

The Vehicle Body Total Road Load block implements a one degree-of-freedom (1DOF) rigid vehicle model using coast-down testing coefficients. You can use this block in a vehicle model to represent the load that the driveline and chassis applies to a transmission or engine. It is suitable for system-level performance, component sizing, fuel economy, or drive cycle tracking studies. The block calculates the dynamic powertrain load with minimal parameterization or computational cost.

You can configure the block for kinematic, force, or total power input.

- Kinematic — Block uses the vehicle longitudinal velocity and acceleration to calculate the tractive force and power.
- Force — Block uses the tractive force to calculate the vehicle longitudinal displacement and velocity.
- Power — Block uses the engine or transmission power to calculate the vehicle longitudinal displacement and velocity.

Dynamics

To calculate the total road load acting on the vehicle, the block implements this equation.

$$F_{road} = a + b\dot{x} + c\dot{x}^2 + mg\sin(\theta)$$

To determine the coefficients a , b , and c , you can use a test procedure similar to the one described in *Road Load Measurement and Dynamometer Simulation Using Coastdown Techniques*. You can also use Simulink® Design Optimization™ to fit the coefficients to measured data.

To calculate the vehicle motion, the block uses Newton's law for rigid bodies.

$$F_{total} = m\ddot{x} + F_{road}$$

Total power input is a product of the total force and longitudinal velocity. Power due to road and gravitational forces is a product of the road force and longitudinal velocity.

$$P_{total} = F_{total}\dot{x}$$

$$P_{road} = F_{road}\dot{x}$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrFxExt	Externally applied force power P_{FxExt}	$P_{FxExt} = F_{total}\dot{x}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrFxDrag	Drag force power P_D	$P_D = -(a + b\dot{x} + c\dot{x}^2)\dot{x}$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	wrStoredGrvty	Rate change in gravitational potential energy P_g	$P_g = -mg\dot{Z}$
		PwrStoredxdot	Rate in change of longitudinal kinetic energy P_{xdot}	$P_{\dot{x}} = m\ddot{x}\dot{x}$

The equations use these variables.

a	Steady-state rolling resistance coefficient
b	Viscous driveline and rolling resistance coefficient
c	Aerodynamic drag coefficient
g	Gravitational acceleration
x	Vehicle longitudinal displacement with respect to ground, in the vehicle-fixed frame
\dot{x}	Vehicle longitudinal velocity with respect to ground, in the vehicle-fixed frame
\ddot{x}	Vehicle longitudinal acceleration with respect to ground, vehicle-fixed frame
m	Vehicle body mass
Θ	Road grade angle
F_{total}	Total force acting on vehicle
F_{road}	Resistive road load due to losses and gravitational load
P_{total}	Total tractive input power
P_{road}	Total power due to losses and gravitational load
\dot{Z}	Vehicle vertical velocity along the vehicle-fixed z-axis

Ports

Input

xdot — Vehicle longitudinal velocity

scalar

Vehicle total longitudinal velocity, \dot{x} , in m/s.

Dependencies

To enable this port, for the **Input Mode** parameter, select Kinematic.

xddot — Vehicle longitudinal acceleration

scalar

Vehicle total longitudinal acceleration, \ddot{x} , in m/s².

Dependencies

To enable this port, for the **Input Mode** parameter, select Kinematic.

PwrTot — Tractive input power

scalar

Tractive input power, P_{total} , in W.

Dependencies

To enable this port, for the **Input Mode** parameter, select Power.

ForceTot — Tractive input force

scalar

Tractive input force, F_{total} , in N.

Dependencies

To enable this port, for the **Input Mode** parameter, select Force.

Grade — Road grade angle

scalar

Road grade angle, θ , in deg.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal				Description	Value	Units
In	Cg	Disp	X	Vehicle CG displacement along earth-fixed X-axis	Computed	m

Signal			Description	Value	Units	
tF rm		Y	Vehicle CG displacement along earth-fixed Y-axis	0	m	
			Z	Vehicle CG displacement along earth-fixed Z-axis	Computed	m
		Vel	Xdot	Vehicle CG velocity along earth-fixed X-axis	Computed	m/s
			Ydot	Vehicle CG velocity along earth-fixed Y-axis	0	m/s
			Zdot	Vehicle CG velocity along earth-fixed Z-axis	Computed	m/s
		Ang	phi	Rotation of vehicle-fixed frame about the earth-fixed X-axis (roll)	0	rad
			theta	Rotation of vehicle-fixed frame about the earth-fixed Y-axis (pitch)	Computed	rad
			psi	Rotation of vehicle-fixed frame about the earth-fixed Z-axis (yaw)	0	rad
		Bd yF rm	Cg	Disp	x	Vehicle CG displacement along the vehicle-fixed x-axis
y	Vehicle CG displacement along the vehicle-fixed y-axis				0	m
z	Vehicle CG displacement along the vehicle-fixed z-axis				0	m
Vel	xdot			Vehicle CG velocity along the vehicle-fixed x-axis	Computed	m/s
	ydot			Vehicle CG velocity along the vehicle-fixed y-axis	0	m/s
	zdot			Vehicle CG velocity along the vehicle-fixed z-axis	0	m/s
Acc	ax			Vehicle CG acceleration along the vehicle-fixed x-axis	Computed	gn
	ay			Vehicle CG acceleration along the vehicle-fixed y-axis	0	gn
	az			Vehicle CG acceleration along the vehicle-fixed z-axis	0	gn
Forc es	Body		Fx	Net force on vehicle CG along the vehicle-fixed x-axis	Computed	N
			Fy	Net force on vehicle CG along the vehicle-fixed y-axis	0	N
			Fz	Net force on vehicle CG along the vehicle-fixed z-axis	0	N
	Ext		Fx	External force on vehicle CG along the vehicle-fixed x-axis	Computed	N

Signal			Description	Value	Units	
		Fy	Fy	External force on vehicle CG along the vehicle-fixed y-axis	0	N
			Fz	External force on vehicle CG along the vehicle-fixed z-axis	0	N
			Drag	Fx	Drag force on vehicle CG along the vehicle-fixed x-axis	Computed
		Fy	Drag force on vehicle CG along the vehicle-fixed y-axis	0	N	
		Fz	Drag force on vehicle CG along the vehicle-fixed z-axis	0	N	
		Grvty	Fx	Gravity force on vehicle CG along the vehicle-fixed x-axis	Computed	N
		Fy	Gravity force on vehicle CG along the vehicle-fixed y-axis	0	N	
		Fz	Gravity force on vehicle CG along the vehicle-fixed z-axis	Computed	N	
		Pwr	PwrExt	Applied external power	Computed	W
	Drag	Power loss due to drag	Computed	W		
	PwrInfo	PwrTransf	PwrFxExt	Externally applied force power	P_{FxExt}	W
PwrTotTrnsfrd		PwrFxDrag	Drag force power	P_D	W	
PwrStored		wrStoredGrvty	Rate change in gravitational potential energy	P_g	W	
		PwrStoredxdot	Rate in change of longitudinal kinetic energy	P_{xdot}	W	

xdot – Vehicle longitudinal velocity

scalar

Vehicle total longitudinal velocity, \dot{x} , in m/s.**Dependencies**To enable this port, for the **Input Mode** parameter, select Power or Force.**ForceTot – Tractive input force**

scalar

Tractive input force, F_{total} , in N.**Dependencies**To enable this port, for the **Input Mode** parameter, select Kinematic.

Parameters

Input Mode — Specify input mode

Kinematic (default) | Force | Power

Specify the input type.

- **Kinematic** — Block uses the vehicle longitudinal velocity and acceleration to calculate the tractive force and power. Use this configuration for powertrain, driveline, and braking system design, or component sizing.
- **Force** — Block uses the tractive force to calculate the vehicle longitudinal displacement and velocity. Use this configuration for system-level performance, fuel economy, or drive cycle tracking studies.
- **Power** — Block uses the engine or transmission power to calculate the vehicle longitudinal displacement and velocity. Use this configuration for system-level performance, fuel economy, or drive cycle tracking studies.

Dependencies

This table summarizes the port and input mode configurations.

Input Mode	Creates Ports
Kinematic	xdot xddot
Force	Force
Power	Power

Mass — Vehicle body mass

1200 (default) | scalar

Vehicle body mass, m , in kg.

Rolling resistance coefficient, a — Rolling

196 (default) | scalar

Steady-state rolling resistance coefficient, a , in N.

Rolling and driveline resistance coefficient, b — Rolling and driveline

2.232 (default) | scalar

Viscous driveline and rolling resistance coefficient, b , in N*s/m.

Aerodynamic drag coefficient, c — Drag

0.389 (default) | scalar

Aerodynamic drag coefficient, c , in N*s²/m.

Gravitational acceleration, g — Gravity

9.81 (default) | scalar

Gravitational acceleration, g , in m/s².

Initial position, x_o — Position 0 (default) | scalar

Vehicle longitudinal initial position, in m.

Initial velocity, xdot_o — Velocity 0 (default) | scalar

Vehicle longitudinal initial velocity with respect to ground, in m/s.

Version History

Introduced in R2017a

References

- [1] Gillespie, Thomas. *Fundamentals of Vehicle Dynamics*. Warrendale, PA: Society of Automotive Engineers (SAE), 1992.
- [2] Light Duty Vehicle Performance And Economy Measure Committee. *Road Load Measurement and Dynamometer Simulation Using Coastdown Techniques*. Standard J1263_201003. SAE International, March 2010.

Extended Capabilities

C/C++ Code Generation

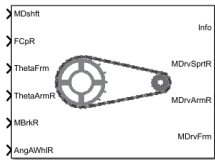
Generate C and C++ code using Simulink® Coder™.

See Also[Drive Cycle Source](#) | [Vehicle Body 1DOF Longitudinal](#) | [Vehicle Body 3DOF Longitudinal](#)

Motorcycle Chain

Implement motorcycle chain

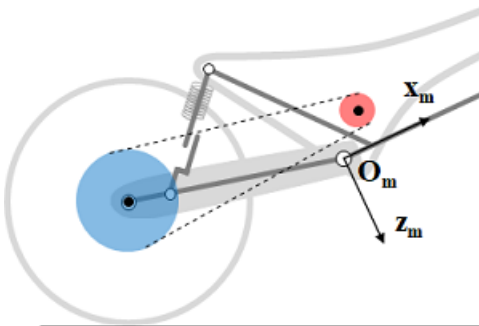
Library: Powertrain Blockset / Drivetrain / Couplings
 Vehicle Dynamics Blockset / Powertrain / Drivetrain / Couplings



Description

The Motorcycle Chain block implements the dynamic effects of a motorcycle chain on the Motorcycle Body Longitudinal In-Plane block, including dynamic tension and moment drive coupling.

This figure shows how the chain relates geometrically to the motorcycle frame, rear arm, and rear wheel.



Frame	Variable in Figure	Description
Motorcycle main frame	O_m	Main frame origin
<ul style="list-style-type: none"> x_m - Forward along vector pointing to front fork z_m - Downward y_m - Orthogonal to motorcycle plane 		

Ports

Input

MDshft – Drive shaft moment on front sprocket
 scalar

Drive shaft moment on front sprocket about y_m , in N·m.

FCpR — Longitudinal and vertical forces at rear wheel contact patch

vector

Longitudinal and vertical forces at rear wheel contact patch O_{CpR} , along i_{CpR} and k_{CpR} , in N. Signal vector dimensions are [1x2] or [2x1].

ThetaFrm — Main frame pitch angle

scalar

Main frame pitch angle, θ_{frm} , in rad.

ThetaArmR — Rear arm pitch angle

scalar

Rear arm pitch angle, θ_{ra} , in rad.

MBrkR — Brake moment at rear wheel

scalar

Brake moment at the rear wheel G_{WhlRr} , about j_{WhlRr} , in N·m.

AngAWhlR — Rear wheel angular acceleration

scalar

Rear wheel angular acceleration, in rad/s².

Output**Info — Bus signal**

bus

Bus signal containing these block calculations.

Signal	Description	Units
FChn	Chain force applied to rear arm	N
AngVSprtR	Angular velocity of rear sprocket	rad/s
MDrvSprtR	Wheel damper moment applied to rear sprocket	N·m
WhlDmpAng	Angle between rear sprocket and rear wheel	rad

MDrvSprtR — Wheel damper moment at rear sprocket

scalar

Wheel damper moment applied to rear sprocket, in N·m.

MDrvArmR — Drive chain moment at rear arm

scalar

Drive chain moment at rear arm O_{ArmRr} , about j_{ArmRr} , in N·m.

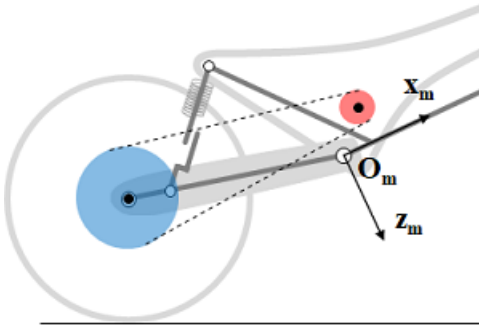
MDrvFrm — Drive chain moment at frame

scalar

Drive chain moment at the frame O_{Frm} , about J_{Frm} , in N·m.

Parameters

This figure shows how the chain relates geometrically to the motorcycle frame, rear arm, and rear wheel.



Front Sprocket

Coordinates, $SprktFrPxz$ — Front sprocket position

$[0.05 \ -0.05]$ (default) | vector

Position of front sprocket, $SprktFrPxz$, along x_m z_m , respectively, in m.

Mass moment of inertia, $SprktFrIyy$ — Front sprocket inertia

0.005 (default) | scalar

Front sprocket mass moment of inertia, $SprktFrIyy$, in $\text{kg}\cdot\text{m}^2$.

Radius, $SprktFrR$ — Front sprocket radius

0.04 (default) | scalar

Front sprocket radius, $SprktFrR$, in m.

Rear Sprocket

Mass moment of inertia, $SprktRrIyy$ — Rear sprocket inertia

0.01 (default) | scalar

Rear sprocket mass moment of inertia, $SprktRrIyy$, in $\text{kg}\cdot\text{m}^2$.

Radius, $SprktRrR$ — Rear sprocket radius

0.12 (default) | scalar

Rear sprocket radius, $SprktRrR$, in m.

Rear Wheel

Mass moment of inertia, $WhlRrIyy$ — Rear wheel inertia

0.66 (default) | scalar

Rear wheel mass moment of inertia, $WhlRrIyy$, in $\text{kg}\cdot\text{m}^2$.

Radius, WhlRrR — Rear wheel radius

0.33 (default) | scalar

Rear wheel radius, *WhlRrR*, in m.**Swing Arm****Arm length, ArmRrLen — Swing arm length**

0.535 (default) | scalar

Arm length, *ArmRrLen*, in m.**Wheel Damper****Stiffness, WhlDmpK — Wheel damper stiffness**

1e4 (default) | scalar

Wheel damper stiffness, *WhlDmpK*, in N/rad.**Damping, WhlDmpC — Wheel damping**

1e2 (default) | scalar

Wheel damper damping, *WhlDmpC*, in N·s/rad.**Equilibrium angle — Wheel damper equilibrium angle**

-15e-3 (default) | scalar

Equilibrium angle, *WhlDmpAng0*, in rad.**Initial Conditions****Rear sprocket angular velocity, SprktRrAngV0 — Angular velocity**

0 (default) | scalar

Rear sprocket angular velocity, *SprktRrAngV0*, in rad/s.**Rear wheel angular velocity, WhlRrAngV0 — Angular velocity**

0 (default) | scalar

Rear wheel angular velocity, *WhlRrAngV0*, in rad/s.

Version History

Introduced in R2021b

References

- [1] Giner, David Moreno. “Symbolic-Numeric Tools for the Analysis of Motorcycle Dynamics. Development of a Virtual Rider for Motorcycles Based on Model Predictive Control.” PhD diss., Universidad Miguel Hernández de Elche, 2016.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

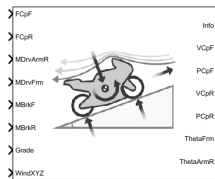
See Also

Motorcycle Body Longitudinal In-Plane

Motorcycle Body Longitudinal In-Plane

Longitudinal in-plane motorcycle vehicle motion

Library: Powertrain Blockset / Vehicle Dynamics
Vehicle Dynamics Blockset / Vehicle Body



Description

The Motorcycle Body Longitudinal In-Plane block implements a longitudinal in-plane motorcycle body model to calculate longitudinal, vertical, and pitch motion. The block accounts for:

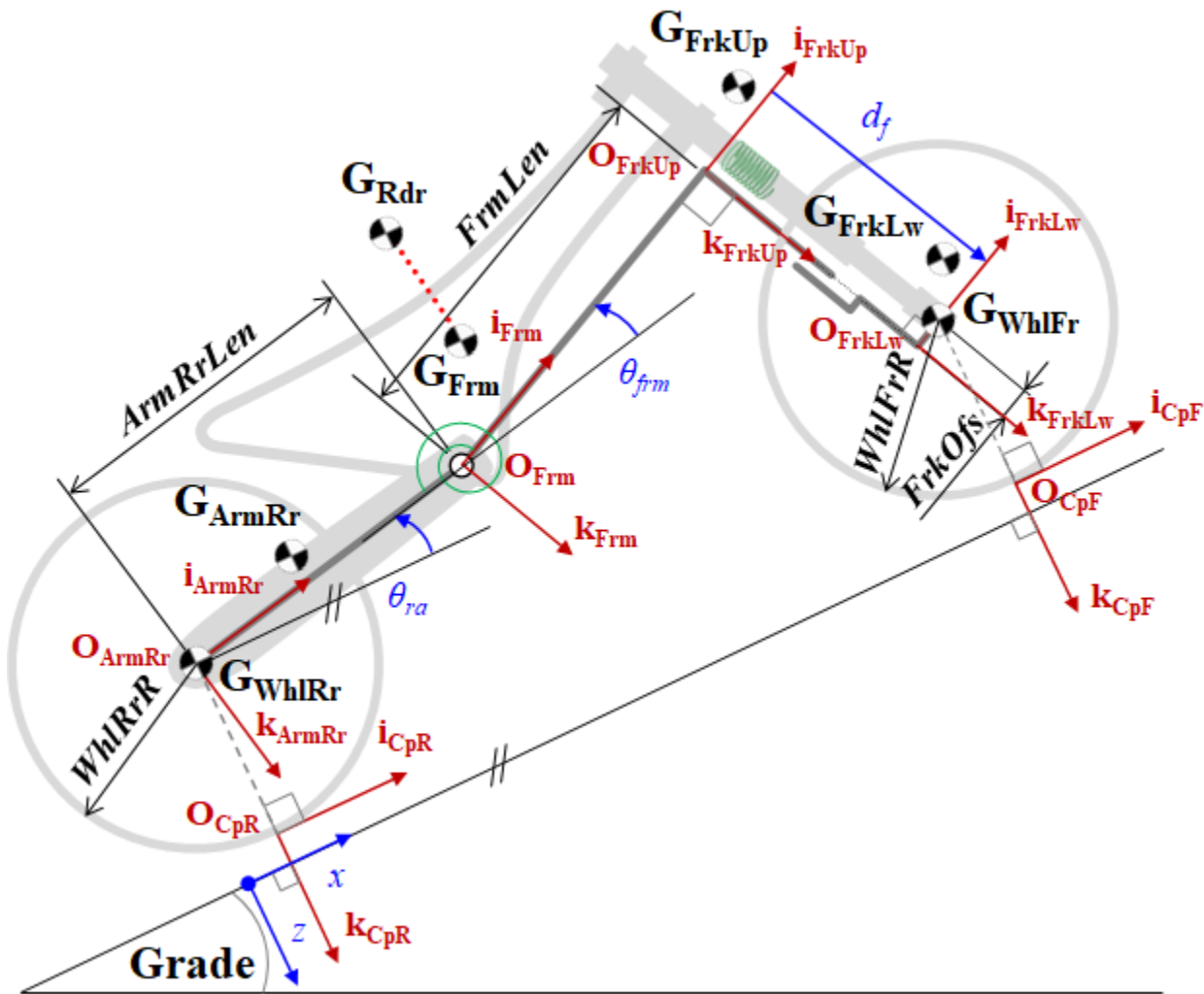
- Mass of the frame, rear arm, front upper fork, front lower fork, front wheel, and rear wheel
- In-plane dynamic effects of the frame, front lower fork, front wheel, rear wheel, rear suspension, front suspension, rear wheel damper, rear arm, and chain
- External forces, external moments, and aerodynamic drag
- Road incline
- Weight distribution between the axles due to acceleration

Consider using this block to represent motorcycle motion in powertrain and fuel economy studies, for example, in studies with heavy braking or acceleration or road profiles that contain larger vertical changes.

The block uses rigid-body vehicle motion, suspension system forces, and wind and drag forces to calculate the forces on the motorcycle frames. The block then determines the position and velocity of motorcycle at the front and rear contact patches.

Layout

To determine the rigid-body motorcycle motion, the block uses right-handed (RH) *Cartesian* reference frames systems attached to the motorcycle. i , j , and k are orthogonal unit vectors attached to the frames.



Frame	Variable in Figure	Description
Road	x, z	Road-fixed coordinate system. x is along road grade, and z points downward.
Motorcycle main frame	O_{Frm}	Main frame origin
	G_{Frm}	Center of mass (CM) of the main frame with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
	G_{Rdr}	CM of the rider with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
	θ_{frm}	Main frame rotation about j_{Frm}
Upper fork	O_{FrkUp}	Upper fork origin
	i_{FrkUp}	Forward along vector given by θ_{frm}
	k_{FrkUp}	Downward

Frame	Variable in Figure	Description
<ul style="list-style-type: none"> j_{FrkUp} - Orthogonal to motorcycle plane 	G_{FrkUp}	CM of the upper fork with respect to O_{FrkUp} , along i_{FrkUp} and k_{FrkUp} , respectively
Lower fork	O_{FrkLw}	Lower fork origin
	G_{FrkLw}	CM of the lower fork with respect to O_{FrkLw} , along i_{FrkLw} and k_{FrkLw} , respectively
Rear arm	O_{ArmRr}	Rear arm origin
	G_{ArmRr}	CM of the rear arm with respect to O_{ArmRr} , along i_{ArmRr} and k_{ArmRr} , respectively
	θ_{ra}	Rear arm rotation about j_{ArmRr}
	<ul style="list-style-type: none"> i_{ArmRr} - Forward along vector given by θ_{ra} k_{ArmRr} - Downward j_{ArmRr} - Orthogonal to motorcycle plane 	
Front wheel contact patch	O_{CpF}	Front wheel contact patch origin
<ul style="list-style-type: none"> i_{CpF} - Forward along vector given by road-fixed x- axis k_{CpF} - Downward along vector given by road-fixed z- axis j_{CpF} - Orthogonal to motorcycle plane 		
Rear wheel contact patch	O_{CpR}	Rear wheel contact patch origin
<ul style="list-style-type: none"> i_{CpR} - Forward along vector given by road-fixed x- axis k_{CpR} - Downward along vector given by road-fixed z- axis j_{CpR} - Orthogonal to motorcycle plane 		

Use the parameters in this table to specify the geometric layout of your motorcycle.

Parameter			Variable in Figure
Initial conditions	Position	Rear contact patch longitudinal coordinate, CpRrX0	O_{CpR} with respect to road-fixed coordinate system, along x
		Rear contact patch vertical coordinate, CpRrZ0	O_{CpR} with respect to road-fixed coordinate system, along z
		Pitch angle of rear arm, ArmRrAng0	θ_{ra}
		Pitch angle of main frame, FrmAng0	θ_{Frm}

Parameter			Variable in Figure
		Fork length, FrkFrL0	d_f
Frame		Center of mass location, FrmCmPxz	G_{Frm} with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
		Length, FrmLen	$FrmLen$
Rider		Center of mass location, RdrCmPxz	G_{Rdr} with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
Front Fork	Upper	Position, FrkUpCmPxz	G_{FrkUp} with respect to O_{FrkUp} , along i_{FrkUp} and k_{FrkUp} , respectively
		Offset, FrkOfs	$FrkOfs$
	Lower	Position, FrkLwCmPxz	G_{FrkLw} with respect to O_{FrkLw} , along i_{FrkLw} and k_{FrkLw} , respectively
Rear Arm		Position, ArmRrCmPxz	G_{ArmRr} with respect to O_{ArmRr} , along i_{ArmRr} and k_{ArmRr} , respectively
		Length, ArmRrLen	$ArmRrLen$
Wheels	Front	Radius, WhlFrR	$WhlFrR$
	Rear	Radius, WhlRrR	$WhlRrR$
Suspension	Front	Equilibrium length, FrkLwL0	d_f
	Rear	Equilibrium angle, ShkRrAng0	θ_{Frm}

Input Signals

You can use these block parameters to create additional input ports. This table summarizes the settings.

Input Signals Pane Parameter	Input Port	Description
External forces	FExt	External longitudinal and vertical forces applied at equivalent rider and motorcycle center of mass (CM).
External moments	MExt	External moment about equivalent rider and motorcycle CM, for example, moment due to rider physical motion.
External front wheel moment	MWhlF	External moment at the front wheel G_{WhlFr} , for example, wheel motors and external intermittent friction-related disturbances.
External rear wheel moment	MWhlR	External moment at the rear wheel G_{WhlRr} , for example, wheel motors and external intermittent friction-related disturbances.
Grade angle	Grade	Road grade angle.
Wind velocity	WindXYZ	Wind speed.
Ambient temperature	Temp	Ambient air temperature. Consider this option if you want to vary the temperature during run-time.

Suspension System

Use the **Suspension type** parameter to specify the type of suspension.

Setting	Description
Simple	Block models the suspension force and moment as a spring-damper system: <ul style="list-style-type: none"> • Suspension force at the upper fork • Suspension moment at the rear arm
User-defined	Input the suspension force and moment: <ul style="list-style-type: none"> • FSuspF - Suspension force at the upper fork • MSuspR - Suspension moment at the rear arm

Wind and Drag Forces

The block subtracts the wind speeds from the vehicle velocity components to obtain a net relative airspeed. To calculate the drag force and moments acting on the motorcycle, the block uses the net relative airspeed.

Power Accounting

The block accounts for the power transferred, not transferred, and stored.

Bus Signal		Description	
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrFxExt	Mechanical power from longitudinal external force
		PwrFzExt	Mechanical power from vertical external force
		PwrMyExt	Mechanical power from external pitch moment
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrFxDrag	Mechanical power loss from longitudinal drag force
		PwrFzDrag	Mechanical power loss from vertical lift
		PwrMyDrag	Mechanical power loss from pitch moment drag
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	PwrStoredGrvty	Rate change in gravitational potential energy
		PwrStoredxdot	Rate of change of longitudinal kinetic energy
		PwrStoredzdot	Rate of change of vertical kinetic energy

Bus Signal		Description
	PwrStoredq	Rate of change of rotational pitch kinetic energy
	PwrStoredFsFzSprng	Stored spring energy from front suspension
	PwrStoredFsRzSprng	Stored spring energy from rear suspension

Ports

Input

FCpF — Longitudinal and vertical forces at front wheel contact patch

vector

Longitudinal and vertical forces at front wheel contact patch O_{CpF} , along i_{CpF} and k_{CpF} , in N. Signal vector dimensions are [1x2] or [2x1].

FCpR — Longitudinal and vertical forces at rear wheel contact patch

vector

Longitudinal and vertical forces at rear wheel contact patch O_{CpR} , along i_{CpR} and k_{CpR} , in N. Signal vector dimensions are [1x2] or [2x1].

MDrvArmR — Drive chain moment at rear arm

scalar

Drive chain moment at rear arm O_{ArmRr} , about j_{ArmRr} , in N·m.

MDrvFrm — Drive chain moment at frame

scalar

Drive chain moment at the frame O_{Frm} , about j_{Frm} , in N·m.

FExt — External longitudinal and vertical forces at frame

vector

External longitudinal and vertical forces applied at equivalent rider and motorcycle center of mass (CM), along i_{Frm} and k_{Frm} , in N. Signal vector dimensions are [1x2] or [2x1].

Dependencies

To create this port, select **External forces**.

MExt — External moment about frame

scalar

External moment about equivalent rider and motorcycle CM, j_{Frm} , for example, moment due to rider physical motion, in N·m.

Dependencies

To create this port, select **External moments**.

MBrkF — Brake moment at front wheel

scalar

Brake moment at the front wheel G_{WhlFr} , about j_{WhlFr} , in N·m.**MBrkR — Brake moment at rear wheel**

scalar

Brake moment at the rear wheel G_{WhlRr} , about j_{WhlRr} , in N·m.**MWhlF — External moment at front wheel**

scalar

External moment at the front wheel G_{WhlFr} , in N·m.**Dependencies**To create this port, select **External front wheel moment**.**MWhlR — External moment at rear wheel**

scalar

External moment at the rear wheel G_{WhlRr} , in N·m.**Dependencies**To create this port, select **External rear wheel moment**.**FSuspF — External suspension force at upper fork**

scalar

External suspension force at upper fork O_{FrkUp} , along k_{FrkUp} , in N.**Dependencies**To create this port, set **Suspension type** to User-defined.**MSuspR — External suspension moment at rear arm**

scalar

External suspension force at upper fork O_{ArmRr} , about j_{ArmRr} , in N·m.**Dependencies**To create this port, set **Suspension type** to User-defined.**Grade — Road grade angle**

scalar

Road grade angle, γ , in deg.**Dependencies**To create this port, select **Grade angle**.**WindXYZ — Wind speed**

array

Wind speed, W_x , W_y , W_z along earth-fixed X-, Y-, and Z-axes, in m/s. Signal vector dimensions are [1x3] or [3x1].

Dependencies

To create this port, select **Wind velocity**.

Temp — Ambient air temperature

scalar

Ambient air temperature, T_{air} , in K. Considering this option if you want to vary the temperature during run-time.

Dependencies

To create this port, select **Ambient temperature**.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal				Signal	Units	
Geom				PosOrgInert	Main frame position along the earth-fixed axes	m
				PosFwBdy	Front wheel center position relative to initial vehicle-fixed wheel position, along the vehicle Z-down X-, Y-, and Z-axes	m
				PosRwBdy	Rear wheel center position relative to initial vehicle-fixed wheel position, along the vehicle Z-down X-, Y-, and Z-axes	m
				AngOrgInert	Main frame rotation about the earth-fixed axes	rad
Frame	Inert	Cg	Disp	X	Vehicle CM displacement along the earth-fixed X-axis	m
				Y	Vehicle CM displacement along the earth-fixed Y-axis	m
				Z	Vehicle CM displacement along the earth-fixed Z-axis	m
	Vel	Xdot	Vehicle CM velocity along the earth-fixed X-axis	m/s		

Signal				Signal	Units		
				Ydot	Vehicle CM velocity along the earth-fixed Y-axis	m/s	
				Zdot	Vehicle CM velocity along the earth-fixed Z-axis	m/s	
				Ang	phi	Rotation of the vehicle-fixed frame about the earth-fixed X-axis (roll)	rad
					theta	Rotation of the vehicle-fixed frame about the earth-fixed Y-axis (pitch)	rad
					psi	Rotation of the vehicle-fixed frame about the earth-fixed Z-axis (yaw)	rad
	BdyFrm	Cg	Disp	x	Vehicle CM position along the road-fixed x-axis	m	
				y	Vehicle CM position along the road-fixed y-axis	m	
				z	Vehicle CM position along the road-fixed z-axis	m	
			Vel	xdot	Vehicle CM velocity along the road-fixed x-axis	m/s	
				ydot	Vehicle CM velocity along the road-fixed y-axis	m/s	
				zdot	Vehicle CM velocity along the road-fixed z-axis	m/s	
			AngVel	p	Vehicle angular velocity about the road-fixed x-axis (roll rate)	rad/s	
				q	Vehicle angular velocity about the road-fixed y-axis (pitch rate)	rad/s	
				r	Vehicle angular velocity about the road-fixed z-axis (yaw rate)	rad/s	
			Acc	ax	Vehicle CM acceleration along the road-fixed x-axis	m/s ²	
				ay	Vehicle CM acceleration along the road-fixed y-axis	m/s ²	
				az	Vehicle CM acceleration along the road-fixed z-axis	m/s ²	
				xddot	Vehicle CM acceleration along the road-fixed x-axis	m/s ²	

Signal				Signal	Units	
			AngAcc	yddot	Vehicle CM acceleration along the road-fixed y-axis	m/s ²
				zddot	Vehicle CM acceleration along the road-fixed z-axis	m/s ²
				pdot	Vehicle angular acceleration about the road-fixed x-axis	rad/s ²
				qdot	Vehicle angular acceleration about the road-fixed y-axis	rad/s ²
				rdot	Vehicle angular acceleration about the road-fixed z-axis	rad/s ²
		Forces	Ext	Fx	External force on vehicle CM along the road-fixed x-axis	N
				Fy	External force on vehicle CM along the road-fixed x-axis	N
				Fz	External force on vehicle CM along the road-fixed x-axis	N
			Drag	Fx	Drag force on vehicle CM along the road-fixed x-axis	N
				Fy	Drag force on vehicle CM along the road-fixed y-axis	N
				Fz	Drag force on vehicle CM along the road-fixed z-axis	N
			Grvty	Fx	Gravity force on vehicle CM along the road-fixed x-axis	N
				Fy	Gravity force on vehicle CM along the road-fixed y-axis	N
				Fz	Gravity force on vehicle CM along the road-fixed z-axis	N
		Moments	Drag	Mx	Drag moment on vehicle CM about the road-fixed x-axis	N·m
				My	Drag moment on vehicle CM about the road-fixed z-axis	N·m

Signal				Signal	Units
			Mz	Drag moment on vehicle CM about the road-fixed z-axis	N·m
		Ext	Mx	External moment on vehicle CG about the road-fixed x-axis	N·m
			My	External moment on vehicle CG about the road-fixed y-axis	N·m
			Mz	External moment on vehicle CG about the road-fixed z-axis	N·m
		Pwr	PwrExt	Applied external power	W
			Drag	Power loss due to drag	W
	PwrInfo	Pwr Trnsfrd	PwrFxExt	Mechanical power from longitudinal external force	W
			PwrFzExt	Mechanical power from vertical external force	W
			PwrMyExt	Mechanical power from external pitch moment	W
		PwrNot Trnsfrd	PwrFxDrag	Mechanical power loss from longitudinal drag force	W
			PwrFzDrag	Mechanical power loss from vertical lift force	W
			PwrMyDrag	Mechanical power loss from pitch moment drag	W
		PwrStored	PwrStoredGrvty	Rate change in gravitational potential energy	W
			PwrStoredxdot	Rate of change of longitudinal kinetic energy	W
			PwrStoredzdot	Rate of change of vertical kinetic energy	W
			PwrStoredq	Rate of change of rotational pitch kinetic energy	W
	Genrl	Vel	xdot	Vehicle CM velocity along the road-fixed x-axis	m/s
			zdot	Vehicle CM velocity along the road-fixed z-axis	m/s
		Ang	thetafrm	Pitch angle of main frame	rad

Signal				Signal		Units	
		AngVel	thetafrmdot		Main frame rotational velocity	rad/s	
		AngAcc	thetafrmdot		Main frame rotational acceleration	rad/s ²	
Whl	Genrl	Frnt	Cp	Disp	x	Front wheel contact patch position along the road-fixed x-axis	m
					z	Front wheel contact patch position along the road-fixed z-axis	m
				Vel	xidot	Front wheel contact patch velocity along the road-fixed x-axis	m/s
					zidot	Front wheel contact patch velocity along the road-fixed z-axis	m/s
				Acc	xiddot	Front wheel contact patch acceleration along the road-fixed x-axis	m/s ²
					ziddot	Front wheel contact patch acceleration along the road-fixed z-axis	m/s ²
				Axl	Vel	xidot	Front wheel axle velocity along the road-fixed x-axis
		zidot	Front wheel axle velocity along the road-fixed z-axis			m/s	
		Rear	Cp	Disp	x	Rear wheel contact patch position along the road-fixed x-axis	m
					z	Rear wheel contact patch position along the road-fixed z-axis	m
				Vel	xidot	Rear wheel contact patch velocity along the road-fixed x-axis	m/s
					zidot	Rear wheel contact patch velocity along the road-fixed z-axis	m/s
				Acc	xiddot	Rear wheel contact patch acceleration along the road-fixed x-axis	m/s ²
					ziddot	Rear wheel contact patch acceleration along the road-fixed z-axis	m/s ²

Signal			Signal			Units	
			Axl	Vel	xdot	Rear wheel axle velocity along the road-fixed x-axis	m/s
					zdot	Rear wheel axle velocity along the road-fixed z-axis	m/s
RearArm	Genrl	Vel	xdot			Rear arm velocity along the road-fixed x-axis	m/s
			zdot			Rear arm velocity along the road-fixed z-axis	m/s
		Ang	thetara			Pitch angle of rear arm	rad
		AngVel	thetaradot			Rear arm rotational velocity	rad/s
		AngAcc	thetaraddot			Rear arm rotational acceleration	rad/s ²
Fork	Genrl	Upr	Vel	xdot		Upper fork velocity along the road-fixed x-axis	m/s
				zdot		Upper fork velocity along the road-fixed z-axis	m/s
		Lwr	Disp	df		Fork length	m
			Vel	xdot		Lower fork velocity along the road-fixed x-axis	m/s
				zdot		Lower fork velocity along the road-fixed z-axis	m/s
				dfdot		Fork length velocity	m/s
			Acc	dfddot		Fork length acceleration	m/s ²
Susp	Genrl	Rear	Moments	Mthetafrm		Rear suspension moment at frame	N·m
		Frnt	Forces	Fdf		Suspensive force at upper fork	N

VCpF – Longitudinal, lateral, and vertical velocity at front wheel contact patch
vector

Longitudinal, lateral, and vertical velocity at front wheel contact patch O_{CpF} , along i_{CpF} and k_{CpF} , in m/s. Signal vector dimensions are [1x3] or [3x1]. The lateral component is set to 0.

PCpF – Longitudinal, lateral, and vertical position at front wheel contact patch
vector

Longitudinal, lateral, and vertical position at front wheel contact patch O_{CpF} , along i_{CpF} and k_{CpF} , in m. Signal vector dimensions are [1x3] or [3x1]. The lateral component is set to 0.

VCpR – Longitudinal, lateral, and vertical velocity at rear wheel contact patch
vector

Longitudinal, lateral, and vertical velocity at rear wheel contact patch O_{CpR} , along i_{CpR} and k_{CpR} , in m/s. Signal vector dimensions are [1x3] or [3x1]. The lateral component is set to 0.

PCpR — Longitudinal, lateral, and vertical position at rear wheel contact patch

vector

Longitudinal, lateral, and vertical position at rear wheel contact patch O_{CpR} , along i_{CpR} and k_{CpR} , in m. Signal vector dimensions are [1x3] or [3x1]. The lateral component is set to 0.

ThetaFrm — Main frame pitch angle

scalar

Main frame pitch angle, θ_{frm} , in rad.

ThetaArmR — Rear arm pitch angle

scalar

Rear arm pitch angle, θ_{ra} , in rad.

Parameters

Options

Suspension type — Type of suspension

Simple (default) | User-defined

Use the **Suspension type** parameter to specify the type of suspension.

Setting	Description
Simple	Block models the suspension force and moment as a spring-damper system: <ul style="list-style-type: none"> • Suspension force at the upper fork • Suspension moment at the rear arm
User-defined	Input the suspension force and moment: <ul style="list-style-type: none"> • FSuspF - Suspension force at the upper fork • MSuspR - Suspension moment at the rear arm

Input signals

External forces — FExt input port

off (default) | on

Specify to create input port FExt.

External moments — MExt input port

off (default) | on

Specify to create input port MExt.

External front wheel moment — MWhlF input port

off (default) | on

Specify to create input port MWhlF. Consider using this port to input external moments such as wheel motors and external intermittent friction-related disturbances.

External rear wheel moment – MWhlR input port

off (default) | on

Specify to create input port MWhlR. Consider using this port to input external moments such as wheel motors and external intermittent friction-related disturbances.

Grade angle – Grade input port

on (default) | off

Specify to create input port Grade.

Wind velocity – WindXYZ input port

on (default) | off

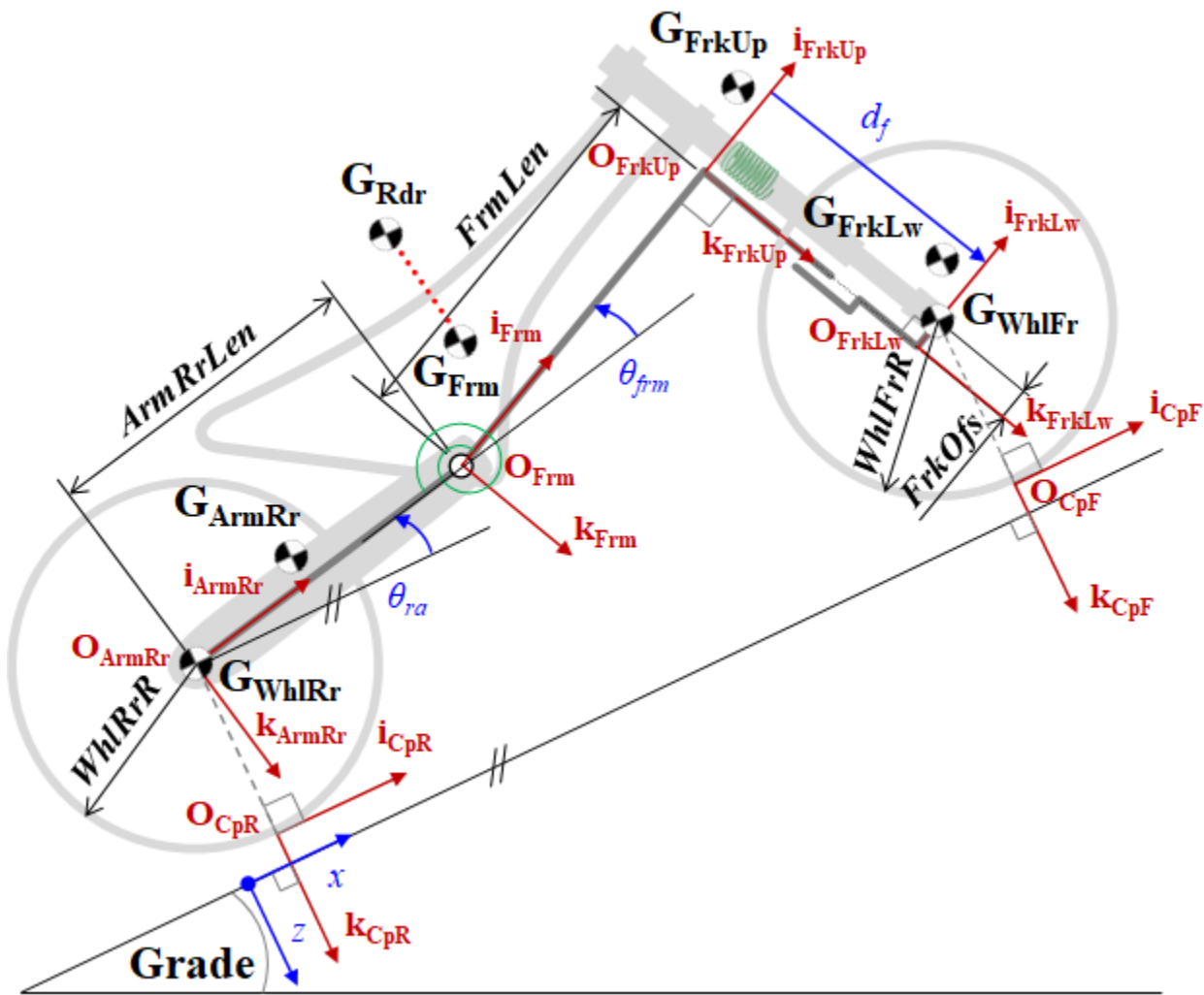
Specify to create input port WindXYZ.

Ambient temperature – Temp input port

off (default) | on

Specify to create input port Temp.

Layout



Use the parameters in this table to specify the geometric layout of your motorcycle.

Parameter		Variable in Figure	
Initial conditions	Position	Rear contact patch longitudinal coordinate, CpRrX0	O_{CpR} with respect to road-fixed coordinate system, along x
		Rear contact patch vertical coordinate, CpRrZ0	O_{CpR} with respect to road-fixed coordinate system, along z
		Pitch angle of rear arm, ArmRrAng0	θ_{ra}
		Pitch angle of main frame, FrmAng0	θ_{Frm}
		Fork length, FrkFrL0	d_f

Parameter			Variable in Figure
Frame	Center of mass location, FrmCmPxz		G_{Frm} with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
	Length, FrmLen		$FrmLen$
Rider	Center of mass location, RdrCmPxz		G_{Rdr} with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively
Front Fork	Upper	Position, FrkUpCmPxz	G_{FrkUp} with respect to O_{FrkUp} , along i_{FrkUp} and k_{FrkUp} , respectively
		Offset, FrkOfs	$FrkOfs$
	Lower	Position, FrkLwCmPxz	G_{FrkLw} with respect to O_{FrkLw} , along i_{FrkLw} and k_{FrkLw} , respectively
Rear Arm	Position, ArmRrCmPxz		G_{ArmRr} with respect to O_{ArmRr} , along i_{ArmRr} and k_{ArmRr} , respectively
	Length, ArmRrLen		$ArmRrLen$
Wheels	Front	Radius, WhlFrR	$WhlFrR$
	Rear	Radius, WhlRrR	$WhlRrR$
Suspension	Front	Equilibrium length, FrkLwL0	d_f
	Rear	Equilibrium angle, ShkRrAng0	θ_{Frm}

Frame

Center of mass location, FrmCmPxz – Frame location

[0.255, -0.02] (default) | vector

Center of mass location of the frame, G_{Frm} . Specified as a vector with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively.

Mass, FrmMass – Frame mass

223 (default) | scalar

Frame mass, $FrmMass$, in kg.

Mass moment of inertia, FrmIyy – Frame inertia

26.2 (default) | scalar

Mass moment of inertia, $FrmIyy$, in $\text{kg}\cdot\text{m}^2$.

Length, FrmLen – Frame length

0.730 (default) | scalar

Length of the frame, $FrmLen$, in m.

Rider

Center of mass location, RdrCmPxz – Rider location

[0.275, -0.61] (default) | vector

Center of mass location of the rider, G_{Rdr} . Specified as a vector with respect to O_{Frm} , along i_{Frm} and k_{Frm} , respectively.

Mass, RdrMass – Rider mass

78 (default) | scalar

Rider mass, $RdrMass$, in kg.**Mass moment of inertia, RdrIyy – Rider inertia**

26.2 (default) | scalar

Rider mass moment of inertia, $RdrIyy$, in kg·m².**Front Fork - Upper****Position, FrkUpCmPxz – Upper fork location**

[0.023, -0.098] (default) | vector

Center of mass location of the upper fork, G_{FrkUp} . Specified as a vector with respect to O_{FrkUp} , along i_{FrkUp} and k_{FrkUp} , respectively.**Mass, FrkUpMass – Upper fork mass**

8.8 (default) | scalar

Upper fork mass, $FrkUpMass$, in kg.**Mass moment of inertia, FrmIyy – Upper fork inertia**

0.14 (default) | scalar

Upper fork mass moment of inertia, $FrkUpIyy$, in kg·m².**Offset, FrkOfs – Upper fork offset**

0.034 (default) | scalar

Upper fork offset, $FrkOfs$, in m.**Front Fork - Lower****Position, FrkLwCmPxz – Lower fork location**

[-0.029, -0.189] (default) | vector

Center of mass location of the lower fork, G_{FrkLw} . Specified as a vector with respect to O_{FrkLw} , along i_{FrkLw} and k_{FrkLw} , respectively.**Mass, FrkLwMass – Lower fork mass**

7.0 (default) | scalar

Lower fork mass, $FrkLwMass$, in kg.**Mass moment of inertia, FrkLwIyy – Lower fork inertia**

0.18 (default) | scalar

Lower fork mass moment of inertia, $FrkLwIyy$, in kg·m².**Rear Arm****Position, ArmRrCmPxz – Rear arm location**

[0.275, -0.052] (default) | vector

Center of mass location of the rear arm, G_{ArmRr} . Specified as a vector with respect to O_{ArmRr} , along i_{ArmRr} and k_{ArmRr} , respectively.

Mass, ArmRrMass — Rear arm mass

10 (default) | scalar

Rear arm mass, $ArmRrMass$, in kg.

Mass moment of inertia, ArmRrIyy — Rear arm inertia

0.8 (default) | scalar

Rear arm mass moment of inertia, $ArmRrIyy$, in $\text{kg}\cdot\text{m}^2$.

Length, ArmRrLen — Rear arm length

0.535 (default) | scalar

Rear arm length, $ArmRrLen$, in m.

Wheels - Front

Mass, WhlFrMass — Front wheel mass

12 (default) | scalar

Front wheel mass, $WhlFrMass$, in kg.

Radius, WhlFrR — Front wheel radius

0.3 (default) | scalar

Front wheel radius, $WhlFrR$, in m.

Wheels - Rear

Mass, WhlRrMass — Rear wheel mass

16.2 (default) | scalar

Rear wheel mass, $WhlRrMass$, in kg.

Radius, WhlRrR — Rear wheel radius

0.33 (default) | scalar

Rear wheel radius, $WhlRrR$, in m.

Suspension - Front

Stiffness, SuspFrK — Front suspension stiffness

25e3 (default) | scalar

Front suspension stiffness at O_{FrkUp} , along k_{FrkUp} , in N/m.

Damping, SuspFrC — Front suspension damping

1250 (default) | scalar

Front suspension damping, at O_{FrkUp} , along k_{FrkUp} , in N·s/m.

Equilibrium length, FrkLwL0 — Front suspension equilibrium length

0.473 (default) | scalar

Front suspension equilibrium length, d_f , in m.

Suspension - Rear

Stiffness, SuspRrK — Rear arm suspension stiffness

1500 (default) | scalar

Rear arm suspension stiffness at O_{ArmRr} , about j_{ArmRr} , in N/rad.

Damping, SuspRrC — Rear arm suspension damping

150 (default) | scalar

Rear arm suspension damping at O_{ArmRr} , about j_{ArmRr} , in N·s/rad.

Equilibrium angle, ShkRrAng0 — Rear suspension equilibrium angle

0 (default) | scalar

Rear suspension equilibrium angle, θ_{Frm} , in rad.

Aerodynamic

Longitudinal drag area, Af — Area

2 (default) | scalar

Effective vehicle cross-sectional area, A_f to calculate the aerodynamic drag force on the vehicle, in m^2 .

Longitudinal drag coefficient, Cd — Drag

.2 (default) | scalar

Air drag coefficient, C_d , dimensionless.

Longitudinal lift coefficient, Cl — Lift

.1 (default) | scalar

Air lift coefficient, C_l , dimensionless.

Longitudinal drag pitch moment, Cpm — Pitch drag

.1 (default) | scalar

Longitudinal drag pitch moment coefficient, C_{pm} , dimensionless.

Pitch moment length, Lcpm — Pitch drag

2 (default) | scalar

Pitch moment length, L_{cpm} , in m.

Environment

Gravitational acceleration, g — Gravity

9.80665 (default) | scalar

Gravitational acceleration, g , in m/s^2 .

Absolute air pressure, Pabs — Pressure

101325 (default) | scalar

Environmental air absolute pressure, P_{abs} , in Pa.

Air temperature, T_{air} – Ambient air temperature

273 (default) | scalar

Ambient air temperature, T_{air} , in K.

Dependencies

To enable this parameter, clear **Ambient temperature**.

Initial conditions

Position

Rear contact patch longitudinal coordinate, $CpRrX0$ – Longitudinal coordinate

0 (default) | scalar

Rear contact patch longitudinal coordinate, O_{CpR} , with respect to road-fixed coordinate system, along x, in m.

Rear contact patch vertical coordinate, $CpRrZ0$ – Vertical coordinate

0 (default) | scalar

Rear contact patch vertical coordinate, O_{CpR} , with respect to road-fixed coordinate system, along z, in m.

Pitch angle of rear arm, $ArmRrAng0$ – Rear arm angle

0.0590379 (default) | scalar

Pitch angle of rear arm, θ_{ra} , in rad.

Pitch angle of main frame, $FrmAng0$ – Angle length

0.377024 (default) | scalar

Pitch angle of main frame, θ_{Frm} , in rad.

Fork length, $FrkFrL0$ – Fork length

0.4262193 (default) | scalar

Fork length, d_f , in m.

Velocity

Longitudinal velocity of rear contact patch – Longitudinal velocity

0 (default) | scalar

Rear contact patch longitudinal coordinate, \dot{O}_{CpR} , with respect to road-fixed coordinate system, along x, in m/s.

Vertical velocity of rear contact patch, $CpRrVz0$ – Vertical velocity

0 (default) | scalar

Vertical velocity of rear contact patch, \dot{O}_{CpR} , with respect to road-fixed coordinate system, along z, in m/s.

Pitch rate of rear arm, ArmRrAngV0 – Pitch rate \emptyset (default) | scalarPitch rate of rear arm, $\dot{\theta}_{ra}$, in rad/s.**Pitch rate of main frame, FrmAngV0 – Pitch rate** \emptyset (default) | scalarPitch rate of main frame, $\dot{\theta}_{Frm}$, in rad/s.**Lower fork deformation velocity, FrkLwV0 – Deformation velocity** \emptyset (default) | scalarLower fork deformation velocity, \dot{d}_f , in m/s.**Coordinate Offsets****Longitudinal offset, longOff – Longitudinal offset** \emptyset (default) | scalar

Vehicle main frame offset along the earth-fixed X-axis, in m.

Lateral offset, latOff – Lateral offset \emptyset (default) | scalar

Vehicle main frame offset along the earth-fixed Y-axis, in m.

Vertical offset, vertOff – Vertical offset \emptyset (default) | scalar

Vehicle main frame offset along the earth-fixed Z-axis, in m.

Roll offset, pitchOff – Roll offset \emptyset (default) | scalar

Vehicle main frame offset about the earth-fixed X-axis, in rad.

Pitch offset, pitchOff – Pitch offset \emptyset (default) | scalar

Vehicle main frame offset about the earth-fixed Y-axis, in rad.

Yaw offset, pitchOff – Yaw offset \emptyset (default) | scalar

Vehicle main frame offset about the earth-fixed Z-axis, in rad.

Version History**Introduced in R2021b**

References

- [1] Giner, David Moreno. "Symbolic-Numeric Tools for the Analysis of Motorcycle Dynamics. Development of a Virtual Rider for Motorcycles Based on Model Predictive Control." PhD diss., Universidad Miguel Hernández de Elche, 2016.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Motorcycle Chain

Topics

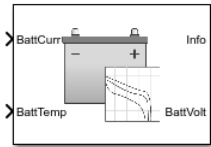
"Conventional Vehicle Spark-Ignition Engine Fuel Economy and Emissions"

Energy Storage Blocks

Datasheet Battery

Lithium-ion, lithium-polymer, or lead-acid battery

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / Datasheet Battery



Description

The Datasheet Battery block implements a lithium-ion, lithium-polymer, or lead-acid battery that you can parameterize using manufacturer data. To create the open-circuit voltage and internal resistance parameters that you need for the block, use the manufacturer discharge characteristics by temperature data. For an example, see “Generate Parameter Data for Datasheet Battery Block”.

To determine the battery output voltage, the block uses lookup tables for the battery open-circuit voltage and the internal resistance. The lookup tables are functions of the state-of charge (SOC) and battery temperature, characterizing the battery performance at various operating points:

$$E_m = f(SOC)$$

$$R_{int} = f(T, SOC)$$

To calculate the voltage, the block implements these equations.

$$V_T = E_m + I_{batt}R_{int}$$

$$I_{batt} = \frac{I_{in}}{N_p}$$

$$V_{out} = \begin{cases} N_s V_T & \text{unfiltered} \\ \frac{V_{out}}{\tau s + 1} & \text{filtered} \end{cases}$$

$$SOC = \frac{1}{Cap_{batt}} \int_0^t I_{batt} dt$$

$$Ld_{AmpHr} = \int_0^t I_{batt} dt$$

Positive current indicates battery discharge. Negative current indicates battery charge.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrLdBatt	Battery network power $V_{batt} = V_{out}$ OR $\frac{V_{out}}{\tau_s + 1}$ $P_{batt} = -V_{batt}I_{batt}$ $P_{LdBatt} = -P_{batt}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrLossBatt	Battery network power loss $P_{LossBatt} = -N_p N_s I_{batt}^2 R_{int}$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredBatt	Battery network power stored $P_{StoredBatt} = P_{Batt} + P_{LossBatt}$

The equations use these variables.

<i>SOC</i>	State-of-charge
<i>E_m</i>	Battery open-circuit voltage
<i>I_{batt}</i>	Per module battery current
<i>P_{LdBatt}</i>	Battery network power
<i>P_{batt}</i>	Battery power
<i>P_{LossBatt}</i>	Battery network power loss
<i>P_{StoredBatt}</i>	Battery network power stored
<i>I_{in}</i>	Combined current flowing from the battery network
<i>R_{int}</i>	Battery internal resistance
<i>N_s</i>	Number of cells in series
<i>N_p</i>	Number of cells in parallel
<i>V_{out}, V_{batt}</i>	Combined voltage of the battery network
<i>V_T</i>	Per module battery voltage
<i>Cap_{batt}</i>	Battery capacity
<i>Ld_{AmpHr}</i>	Battery energy

Ports

Inputs

CapInit — Battery capacity

scalar

Rated battery capacity at the nominal temperature, *Cap_{batt}*, in Ah.

Dependencies

To create this port, select External Input for the **Initial battery capacity** parameter.

BattCurr – Battery load current

scalar

Combined current flowing from the battery network, I_{in} , in A.

BattTemp – Battery temperature

scalar

Temperature measured at the battery housing, T , in K.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
BattCurr		Combined current flowing from the battery network	I_{batt}	A	
BattAmpHr		Battery energy	Ld_{AmpHr}	A*h	
BattSoc		State-of-charge capacity	SOC	NA	
BattVolt		Combined voltage of the battery network	V_{out}	V	
BattPwr		Battery network power	P_{batt}	W	
PwrInfo	PwrTrnsfrd	PwrLdBatt	Battery network power	P_{LdBatt}	W
	PwrNotTrnsfrd	PwrLossBatt	Battery network power loss	$P_{LossBatt}$	W
	PwrStored	PwrStoredBatt	Battery network power stored	$P_{StoredBatt}$	W

BattVolt – Battery output voltage

scalar

Combined voltage of the battery network, V_{out} , in V.

Parameters

Block Options

Initial battery capacity – Input or parameter

Parameter (default) | External Input

Initial battery capacity, Cap_{batt} , in Ah.

Dependencies

Block Parameter Initial battery capacity Option	Creates
External Input	Input port CapInit
Parameter	Parameter Initial battery capacity, BattCapInit

Output battery voltage – Unfiltered or Filter

Unfiltered (default) | Filtered

Select Filtered to apply a first-order filter to the output batter voltage.

Dependencies

Setting **Output battery voltage** parameter to Filtered creates these parameters:

- **Output battery voltage time constant, Tc**
- **Output battery voltage initial value, Vinit**

Rated capacity at nominal temperature, BattChargeMax – Constant

100 (default) | scalar

Rated battery capacity at the nominal temperature, in Ah.

Open circuit voltage table data, Em – 1-D lookup table

1-by-P matrix

Open-circuit voltage data curve, E_m , as a function of the discharged capacity for P operating points, in V.

Open circuit voltage breakpoints 1, CapLUTBp – Breakpoints

1-by-P matrix

Discharge capacity breakpoints for P operating points, dimensionless.

Although this parameter is the same as the **Battery capacity breakpoints 2, CapSOCBp** parameter, the block uses unique parameters for calibration flexibility.

Internal resistance table data, RInt – 2-D lookup table

N-by-M matrix

Internal resistance map, R_{int} , as a function of N temperatures and M SOCs, in ohms.

Battery temperature breakpoints 1, BattTempBp – Breakpoints

[243.1 253.1 263.1 273.1 283.1 298.1 313.1] (default) | 1-by-N matrix

Battery temperature breakpoints for N temperatures, in K.

Battery capacity breakpoints 2, CapSOCBp – Breakpoints

[0 0.2 0.4 0.6 0.8 1] (default) | 1-by-M matrix

Battery capacity breakpoints for M SOCs, dimensionless.

Although this parameter is the same as the **Open circuit voltage breakpoints 1, CapLUTBp** parameter, the block uses unique parameters for calibration flexibility.

Number of cells in series, N_s – Integer

1 (default) | scalar

Number of cells in series, dimensionless, N_s .

Number of cells in parallel, N_p – Integer

1 (default) | scalar

Number of cells in parallel, dimensionless, N_p .

Initial battery capacity, BattCapInit – Capacity

100 (default) | scalar

Initial battery capacity, Cap_{batt} , in Ah.

Dependencies

Block Parameter Initial battery capacity Option	Creates
External Input	Input port CapInit
Parameter	Parameter Initial battery capacity, BattCapInit

Output battery voltage time constant, T_c – Filter time constant

1/1000 (default) | scalar

Output battery voltage time constant, T_c , in s. Used in a first-order voltage filter.

Dependencies

Setting **Output battery voltage** parameter to Filtered creates these parameters:

- **Output battery voltage time constant, T_c**
- **Output battery voltage initial value, V_{init}**

Output battery voltage initial value – Filter initial voltage

4.221 (default) | scalar

Output battery voltage initial value, V_{init} , in V. Used in a first-order voltage filter.

Dependencies

Setting **Output battery voltage** parameter to Filtered creates these parameters:

- **Output battery voltage time constant, T_c**
- **Output battery voltage initial value, V_{init}**

Version History

Introduced in R2017a

References

- [1] Arrhenius, S.A. "Über die Dissociationswärme und den Einfluß der Temperatur auf den Dissociationsgrad der Elektrolyte." *Journal of Physical Chemistry*. 4 (1889): 96-116.
- [2] Connors, K. *Chemical Kinetics*. New York: VCH Publishers, 1990.
- [3] Ji, Yan, Yancheng Zhang, and Chao-Yang Wang. *Journal of the Electrochemical Society*. Volume 160, Issue 4 (2013), A636-A649.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Estimation Equivalent Circuit Battery | Equivalent Circuit Battery

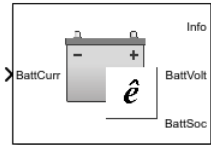
Topics

"Generate Parameter Data for Datasheet Battery Block"
Battery Modeling

Estimation Equivalent Circuit Battery

Resistor-capacitor (RC) circuit battery that creates lookup tables

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / Network Battery



Description

The Estimation Equivalent Circuit Battery block implements a resistor-capacitor (RC) circuit battery model that you can use to create lookup tables for the Equivalent Circuit Battery block. The lookup tables are functions of the state-of-charge (SOC).

The Estimation Equivalent Circuit Battery block calculates the combined voltage of the network battery using parameter lookup tables. The tables are functions of the SOC. To acquire the SOC, the block integrates the charge and discharge currents.

Specifically, the block implements these parameters as lookup tables that are functions of the SOC:

- Series resistance, $R_o=f(SOC)$
- Battery open-circuit voltage, $E_m=f(SOC)$
- Network resistance, $R_n=f(SOC)$
- Network capacitance, $C_n=f(SOC)$

To calculate the combined voltage of the battery network, the block uses these equations.

$$V_T = E_m - I_{batt}R_o - \sum_1^n V_n$$

$$V_n = \int_0^t \left[\frac{I_{batt}}{C_n} - \frac{V_n}{R_n C_n} \right] dt$$

$$SOC = \frac{-1}{C_{batt}} \int_0^t I_{batt} dt$$

$$I_{batt} = I_{in}$$

$$V_{out} = V_T$$

Positive current indicates battery discharge. Negative current indicates battery charge.

The equations use these variables.

SOC	State-of-charge
E_m	Battery open-circuit voltage

I_{batt}	Per module battery current
I_{in}	Combined current flowing from the battery network
R_o	Series resistance
n	Number of RC pairs in series
V_{out}, V_T	Combined voltage of the battery network
V_n	Voltage for n -th RC pair
R_n	Resistance for n -th RC pair
C_n	Capacitance for n -th RC pair
C_{batt}	Battery capacity

Ports

Inputs

BattCurr – Battery network current

scalar

Combined current flowing from the battery network, I_{in} , in A.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable	Units
CapVolt	Voltage for n -th RC pair	V_n	V

BattVolt – Battery output voltage

scalar

Combined voltage of the battery network, V_{out} , in V.

BattSoc – Battery SOC

scalar

Battery state-of-charge, SOC .

Parameters

Core Battery

Number of series RC pairs – RC pairs

1 (default) | 2 | 3 | 4 | 5

Number of series RC pairs. For lithium, typically 1 or 2.

Open circuit voltage Em table data, Em – Voltage table

[3.8 3.8 3.8 3.8 3.8 3.8] (default) | array

Open-circuit voltage table, E_m , in V. Function of SOC.

Series resistance table data, R0 — Resistance
[0.01 0.01 0.01 0.01 0.01 0.01] (default) | array

Series resistance table, R_o , in ohms. Function of SOC.

State of charge breakpoints, SOC_BP — SOC breakpoints
[0 .2 .4 .6 .8 1] (default) | vector

State-of-charge (SOC) breakpoints, dimensionless.

Battery capacity, BattCap — Capacity
27.6250 (default) | scalar

Battery capacity, C_{batt} , in Ah.

Initial battery capacity, BattCapInit — Capacity
27.6250 (default) | scalar

Initial battery capacity, C_{batt0} , in Ah.

Initial capacitor voltage, InitialCapVoltage — Voltage
0 (default) | vector

Initial capacitor voltage, in V. Dimension of vector must equal the **Number of series RC pairs**.

R and C Table Data

Network resistance table data, Rn — Lookup table
[0.005 0.005 0.005 0.005 0.005 0.005] (default) | array

Network resistance table data for n -th RC pair, as a function of SOC, in ohms.

Network capacitance table data, Cn — Lookup table
[10000 10000 10000 10000 10000 10000] (default) | array

Network capacitance table data for n -th RC pair, as a function of SOC, in F.

Cell Limits

Upper Integrator Voltage Limit, Vu — Maximum
Inf (default) | scalar

Upper voltage limit, in V.

Lower Integrator Voltage Limit, Vl — Minimum
Inf (default) | scalar

Lower voltage limit, in V.

Version History

Introduced in R2017a

References

- [1] Ahmed, R., J. Gazzarri, R. Jackey, S. Onori, S. Habibi, et al. "Model-Based Parameter Identification of Healthy and Aged Li-ion Batteries for Electric Vehicle Applications." *SAE International Journal of Alternative Powertrains*. doi:10.4271/2015-01-0252, 4(2):2015.
- [2] Gazzarri, J., N. Shrivastava, R. Jackey, and C. Borghesani. "Battery Pack Modeling, Simulation, and Deployment on a Multicore Real Time Target." *SAE International Journal of Aerospace*. doi:10.4271/2014-01-2217, 7(2):2014.
- [3] Huria, T., M. Ceraolo, J. Gazzarri, and R. Jackey. "High fidelity electrical model with thermal dependence for characterization and simulation of high power lithium battery cells." *IEEE® International Electric Vehicle Conference*. March 2012, pp. 1-8.
- [4] Huria, T., M. Ceraolo, J. Gazzarri, and R. Jackey. "Simplified Extended Kalman Filter Observer for SOC Estimation of Commercial Power-Oriented LFP Lithium Battery Cells." *SAE Technical Paper 2013-01-1544*. doi:10.4271/2013-01-1544, 2013.
- [5] Jackey, R. "A Simple, Effective Lead-Acid Battery Modeling Process for Electrical System Component Selection." *SAE Technical Paper 2007-01-0778*. doi:10.4271/2007-01-0778, 2007.
- [6] Jackey, R., G. Plett, and M. Klein. "Parameterization of a Battery Simulation Model Using Numerical Optimization Methods." *SAE Technical Paper 2009-01-1381*. doi:10.4271/2009-01-1381, 2009.
- [7] Jackey, R., M. Saginaw, T. Huria, M. Ceraolo, P. Sanghvi, and J. Gazzarri. "Battery Model Parameter Estimation Using a Layered Technique: An Example Using a Lithium Iron Phosphate Cell." *SAE Technical Paper 2013-01-1547*. Warrendale, PA: SAE International, 2013.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Datasheet Battery | Equivalent Circuit Battery

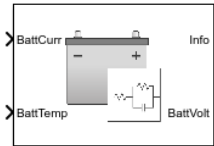
Topics

"Generate Parameter Data for Equivalent Circuit Battery Block"
Battery Modeling

Equivalent Circuit Battery

Resistor-capacitor (RC) circuit battery

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / Network Battery



Description

The Equivalent Circuit Battery block implements a resistor-capacitor (RC) circuit battery that you can parameterize using equivalent circuit modeling (ECM). To simulate the state-of-charge (SOC) and terminal voltage, the block uses load current and internal core temperature.

The Equivalent Circuit Battery block calculates the combined voltage of the network battery using parameter lookup tables. The tables are functions of the SOC and battery temperature. You can use the Estimation Equivalent Circuit Battery block to help create the lookup tables.

Specifically, the Equivalent Circuit Battery block implements these parameters as lookup tables that are functions of the SOC and battery temperature:

- Series resistance, $R_o=f(SOC,T)$
- Battery open-circuit voltage, $E_m=f(SOC,T)$
- Battery capacity, $C_{batt}=f(T)$
- Network resistance, $R_n=f(SOC,T)$
- Network capacitance, $C_n=f(SOC,T)$

To calculate the combined voltage of the battery network, the block uses these equations.

$$V_T = E_m - I_{batt}R_0 - \sum_1^n V_n$$

$$V_n = \int_0^t \left[\frac{I_{batt}}{C_n} - \frac{V_n}{R_n C_n} \right] dt$$

$$SOC = \frac{-1}{C_{batt}} \int_0^t I_{batt} dt$$

$$I_{batt} = \frac{I_{in}}{N_p}$$

$$V_{out} = N_s V_T$$

$$P_{BattLoss} = I_{batt}^2 R_0 + \sum_1^n \frac{V_n^2}{R_n}$$

$$Ld_{AmpHr} = \int_0^t I_{batt} dt$$

Positive current indicates battery discharge. Negative current indicates battery charge.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrLdBatt	Battery network power $V_{batt} = V_{out}$ OR $\frac{V_{out}}{\tau s + 1}$ $P_{batt} = -V_{batt} I_{batt}$ $P_{LdBatt} = -P_{batt}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrLossBatt	Battery network power loss $P_{LossBatt} =$ $- \left(I_{batt}^2 R_0 + \sum_1^n \frac{V_n^2}{R_n} \right)$
	PwrStored — Stored energy rate of change • Positive signals indicate an increase • Negative signals indicate a decrease	PwrStoredBatt	Battery network power stored $P_{StoredBatt} = P_{Batt} + P_{LossBatt}$

The equations use these variables.

SOC State-of-charge

E_m	Battery open-circuit voltage
I_{batt}	Per module battery current
I_{in}	Combined current flowing from the battery network
R_o	Series resistance
N_p	Number parallel branches
N_p	Number of RC pairs in series
V_{out}, V_T	Combined voltage of the battery network
V_n	Voltage for n -th RC pair
R_n	Resistance for n -th RC pair
C_n	Capacitance for n -th RC pair
C_{batt}	Battery capacity
P_{batt}	Battery power
$P_{LossBatt}$	Negative of battery network power loss
$P_{BattLoss}$	Battery network power loss
$P_{StoredBatt}$	Battery network power stored
P_{LdBatt}	Battery network power
T	Battery temperature

Ports

Inputs

CapInit – Battery capacity

scalar

Rated battery capacity at the nominal temperature, Cap_{batt} , in Ah.

Dependencies

To create this port, select External Input for the **Initial battery capacity** parameter.

BattCurr – Battery network current

scalar

Combined current flowing from the battery network, I_{in} , in A.

BattTemp – Battery temperature

scalar

Battery temperature, T , in K.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
BattCurr		Combined current flowing from the battery network	I_{batt}	A	
BattAmpHr		Battery energy	Ld_{AmpHr}	A*h	
BattSoc		State-of-charge capacity	SOC	NA	
BattVolt		Combined voltage of the battery network	V_{out}	V	
BattPwr		Battery power	P_{batt}	W	
PwrInfo	PwrTrnsfrd	PwrLdBatt	Battery network power	P_{LdBatt}	W
	PwrNotTrnsfrd	PwrLossBatt	Battery network power loss	$P_{LossBatt}$	W
	PwrStored	PwrStoredBatt	Battery network power stored	$P_{StoredBatt}$	W

BattVolt – Battery output voltage

scalar

Combined voltage of the battery network, V_{out} , in V.

Parameters

Block Options

Initial battery capacity – Input or parameter

Parameter (default) | External Input

Initial battery capacity, Cap_{batt} , in Ah.

Dependencies

Block Parameter Initial battery capacity Option	Creates
External Input	Input port CapInit
Parameter	Parameter Initial battery capacity, BattCapInit

Output battery voltage – Unfiltered or Filter

Unfiltered (default) | Filtered

Select Filtered to apply a first-order filter to the output batter voltage.

Dependencies

Setting **Output battery voltage** parameter to Filtered creates these parameters:

- **Output battery voltage time constant, Tc**
- **Output battery voltage initial value, Vinit**

Core Battery

Number of series RC pairs – RC pairs

1 (default) | 2 | 3 | 4 | 5

Number of series RC pairs. For lithium, typically 1 or 2.

Open circuit voltage Em table data, Em – Voltage table

[3.5042 3.5136; 3.5573 3.5646; 3.6009 3.6153; 3.6393 3.6565; 3.6742 3.6889; 3.7121 3.7214; 3.7937 3.8078; 3.8753 3.8945; 3.97 3.9859; 4.0764 4.0821; 4.1924 4.193] (default) | array

Open circuit voltage table, E_m , in V. Function of SOC and battery temperature.

Series resistance table data, R0 – Resistance

array

Series resistance table, R_o , in ohms. Function of SOC and battery temperature.

State of charge breakpoints, SOC_BP – SOC breakpoints

[0 0.1 0.2 0.3 0.4 0.5 0.6 0.7 0.8 0.9 1] (default) | vector

State-of-charge (SOC) breakpoints, dimensionless.

Temperature breakpoints, Temperature_BP – Battery

[293.15 313.15] (default) | vector

Battery temperature breakpoints, K.

Battery capacity table, BattCap – Capacity

[28 28] (default) | array

Battery capacity, C_{batt} , in Ah. Function of battery temperature.

Initial battery capacity, BattCapInit – Capacity

28 (default) | scalar

Initial battery capacity, Cap_{batt} , in Ah.

Dependencies

Block Parameter Initial battery capacity Option	Creates
External Input	Input port CapInit
Parameter	Parameter Initial battery capacity, BattCapInit

Initial capacitor voltage, InitialCapVoltage – Voltage

0 (default) | array

Initial capacitor voltage, in V. Dimension of vector must equal the **Number of series RC pairs**.

Output battery voltage time constant, Tc – Filter time constant

1/1000 (default) | scalar

Output battery voltage time constant, T_c , in s. Used in a first-order voltage filter.

Dependencies

Setting **Output battery voltage** parameter to **Filtered** creates these parameters:

- **Output battery voltage time constant, T_c**
- **Output battery voltage initial value, V_{init}**

Output battery voltage initial value, V_{init} – Filter initial voltage

4.193 (default) | scalar

Output battery voltage initial value, V_{init} , in V. Used in a first-order voltage filter.

Dependencies

Setting **Output battery voltage** parameter to **Filtered** creates these parameters:

- **Output battery voltage time constant, T_c**
- **Output battery voltage initial value, V_{init}**

R and C Table Data

Network resistance table data, R_n – Lookup table

[0.010342 0.0012244; 0.0067316 0.0011396; 0.0051156 0.0012661; 0.0043447 0.0012265; 0.0038826 0.0011163; 0.0034226 0.0009968; 0.003346 0.0011458; 0.0033222 0.001345; 0.0033201 0.0013091; 0.0032886 0.0010986; 0.0028114 0.0010309] (default) | array

Network resistance table data for n -th RC pair, in ohms, as a function of SOC and battery temperature.

Network capacitance table data, C_n – Lookup table

[2287.7 11897; 6122 24515; 18460 42098; 20975 44453; 15254 33098; 10440 24492; 13903 32975; 16694 40007; 15784 35937; 12165 26430; 9118 24795] (default) | array

Network capacitance table data for n -th RC pair, in F, as a function of SOC and battery temperature.

Cell Limits

Upper integrator voltage limit, V_u – Maximum

-Inf (default) | scalar

Upper voltage limit, in V.

Lower integrator voltage limit, V_l – Minimum

-Inf (default) | scalar

Lower voltage limit, in V.

Version History

Introduced in R2017a

References

- [1] Ahmed, R., J. Gazzarri, R. Jackey, S. Onori, S. Habibi, et al. "Model-Based Parameter Identification of Healthy and Aged Li-ion Batteries for Electric Vehicle Applications." *SAE International Journal of Alternative Powertrains*. doi:10.4271/2015-01-0252, 4(2):2015.
- [2] Gazzarri, J., N. Shrivastava, R. Jackey, and C. Borghesani. "Battery Pack Modeling, Simulation, and Deployment on a Multicore Real Time Target." *SAE International Journal of Aerospace*. doi:10.4271/2014-01-2217, 7(2):2014.
- [3] Huria, T., M. Ceraolo, J. Gazzarri, and R. Jackey. "High fidelity electrical model with thermal dependence for characterization and simulation of high power lithium battery cells." *IEEE International Electric Vehicle Conference*. March 2012, pp. 1-8.
- [4] Huria, T., M. Ceraolo, J. Gazzarri, and R. Jackey. "Simplified Extended Kalman Filter Observer for SOC Estimation of Commercial Power-Oriented LFP Lithium Battery Cells." *SAE Technical Paper 2013-01-1544*. doi:10.4271/2013-01-1544, 2013.
- [5] Jackey, R. "A Simple, Effective Lead-Acid Battery Modeling Process for Electrical System Component Selection." *SAE Technical Paper 2007-01-0778*. doi:10.4271/2007-01-0778, 2007.
- [6] Jackey, R., G. Plett, and M. Klein. "Parameterization of a Battery Simulation Model Using Numerical Optimization Methods." *SAE Technical Paper 2009-01-1381*. doi:10.4271/2009-01-1381, 2009.
- [7] Jackey, R., M. Saginaw, T. Huria, M. Ceraolo, P. Sanghvi, and J. Gazzarri. "Battery Model Parameter Estimation Using a Layered Technique: An Example Using a Lithium Iron Phosphate Cell." *SAE Technical Paper 2013-01-1547*. Warrendale, PA: SAE International, 2013.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Datasheet Battery | Estimation Equivalent Circuit Battery

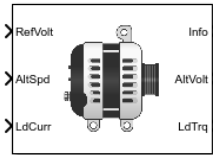
Topics

"Generate Parameter Data for Equivalent Circuit Battery Block"
Battery Modeling

Reduced Lundell Alternator

Reduced Lundell (claw-pole) alternator with an external voltage regulator

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / Alternator



Description

The Reduced Lundell Alternator block implements a reduced Lundell (claw-pole) alternator with an external voltage regulator. The back-electromotive force (EMF) voltage is proportional to the input velocity and field current. The motor operates as a source torque to the internal combustion engine.

Use the Reduced Lundell Alternator block:

- To model an automotive electrical system
- In an engine model with a front-end accessory drive (FEAD)

The calculated motor shaft torque is in the opposite direction of the engine speed. You can:

- Tune the external voltage regulator to a desired bandwidth. The stator current and two diode drops reduce the stator voltage.
- Filter the load current to desired bandwidth. The load current has a lower saturation of 0 A.

The Reduced Lundell Alternator block implements equations for the electrical, control, and mechanical systems that use these variables.

Electrical

To calculate voltages, the block uses these equations.

Calculation	Equations
Alternator output voltage	$v_s = K_v i_f \omega - R_s i_s - 2V_d$
Field winding voltage	$v_f = R_f i_f + L_f \frac{di_f}{dt}$

Control

The controller assumes no resistance or voltage drop.

Calculation	Equations
Field winding voltage transform	$V_f(s) = R_f I_f(s) + sL_f I_f(s)$
Field winding current transform	$I_f(s) = \frac{V_f(s)}{(R_f + sL_f)}$

Calculation	Equations
Open loop electrical transfer function	$G(s) = \frac{V_s(s)}{V_f(s)} = \frac{K_v \omega}{(R_f + sL_f)}$
Open loop voltage regulator transfer function	$G_C(s) = \frac{V_f(s)}{V_{ref}(s)}$
Closed loop transfer function	$T(s) = \frac{G(s)G_C(s)}{1 + G(s)G_C(s)}$
Closed loop controller design	$T(s) = \frac{1}{\tau s + 1} \rightarrow G(s)G_C(s) = \frac{1}{\tau s}$ $G_C(s) = K_g \left(K_p + \frac{K_i}{s} \right)$ $G(s)G_C(s) = \frac{K_v \omega}{(R_f + sL_f)} K_g \left(K_p + \frac{K_i}{s} \right)$ $K_p = L_f, K_i = R_f, \text{ and } K_g = \frac{2\pi f}{K_v \omega}$

Mechanical

To calculate torques, the block uses these equations.

Calculation	Equations
Electrical torque	$\tau_{elec} = (K_v i_f \omega) i_{load}$
Frictional torque	$\tau_{friction} = K_b \omega$
Windage torque	$\tau_{windage} = K_w \omega^2$
Torque at start	$\tau_{start} = K_c$ when $\omega = 0$
Motor shaft torque	$\tau_{mech} = \tau_{elec} + \tau_{friction} + \tau_{windage} + \tau_{start}$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrMtr	Mechanical power P_{mot}	$P_{mot} = \omega \tau_{mech}$
		PwrBus	Electrical power P_{bus}	$P_{bus} = -v_s i_{load}$

Bus Signal		Description	Variable	Equations	
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrLoss	Motor power loss	P_{loss}	$P_{loss} = -(P_{mot} + P_{bus} - P_{ind})$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	PwrInd	Electrical winding loss	P_{ind}	$P_{ind} = L_f i_f \frac{di_f}{dt}$

The equations use these variables.

v_{ref}	Alternator output voltage command
v_f	Field winding voltage
i_f	Field winding current
i_s	Stator winding current
V_d	Diode voltage drop
R_f	Field winding resistance
R_s	Stator winding resistance
L_f	Field winding inductance
K_v	Voltage constant
F_v	Voltage regulator bandwidth
F_c	Input current filter bandwidth
V_{fmax}	Field control voltage upper saturation limit
V_{fmin}	Field control voltage lower saturation limit
K_c	Coulomb friction coefficient
K_b	Viscous friction coefficient
K_w	Windage coefficient
ω	Motor shaft angular speed
i_{load}	Alternator load current
v_s	Alternator output voltage
τ_{mech}, T_{mech}	Motor shaft torque

Ports

Inputs

RefVolt — Alternator output voltage command

scalar

Alternator output voltage command, in V.

AltSpd — Angular speed

scalar

Motor shaft input angular speed, in rad/s.

LdCurr — Alternator load current

scalar

Alternator load current, in A.

Do not connect the port to the alternator rated current, which is a constant value. The block uses the alternator load current as the stator winding current, i_s , to determine the alternator voltage and motor torque. If you connect the port to the rated alternator current, the block does not model the dynamic effect of load current changes on the voltage and motor torque.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
FldVolt		Field winding voltage	A	
FldFlux		Field flux	Wb	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	W
		PwrBus	Electrical power	W
	PwrNotTrnsfrd	PwrLoss	Motor power loss	W
	PwrStored	PwrInd	Electrical winding loss	W

AltVolt — Alternator output voltage

scalar

Alternator output voltage, in V.

LdTrq — Motor shaft torque

scalar

Motor shaft torque, in N·m.

Parameters

Machine Configuration

Voltage constant, K_v — Constant

.1 (default) | scalar

Voltage constant, in V/rad/s.

Field winding resistance, R_f — Resistance

0.2 (default) | scalar

Field winding resistance, in ohm.

Field winding inductance, L_f — Inductance

0.002 (default) | scalar

Field winding inductance, in H.

Stator winding resistance, R_s — Resistance

0.01 (default) | scalar

Stator winding resistance, in ohm.

Diode voltage drop, V_d — Voltage

0.7 (default) | scalar

Diode voltage drop, in V.

Voltage Regulator

Regulator bandwidth, F_v — Bandwidth

2000 (default) | scalar

The regulator bandwidth, in Hz.

Current filter bandwidth, F_c — Bandwidth

1000 (default) | scalar

The current filter bandwidth, in Hz.

Field voltage max, V_{fmax} — Maximum field voltage

100 (default) | scalar

The maximum field voltage, in V.

Field voltage min, V_{fmin} — Minimum field voltage

-100 (default) | scalar

The minimum field voltage, in V.

Mechanical Losses

Coulomb friction, K_c — Friction

0 (default) | scalar

Coulomb friction, in N·m.

Viscous friction, Kb — Friction

0 (default) | scalar

Viscous friction, in N·m/rad/s.

Windage, Kw — Windage

0 (default) | scalar

Windage, in N·m/rad²/s².

Version History

Introduced in R2017a

References

[1] Krause, P. C. *Analysis of Electric Machinery*. New York: McGraw-Hill, 1994.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

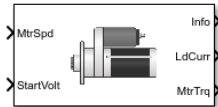
See Also

Starter

Starter

Starter as a DC motor

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / Starter



Description

The Starter block implements a starter assembly as a separately excited DC motor, permanent magnet DC motor, or series connection DC motor. The motor operates as a torque source to an internal combustion engine.

Use the Starter block:

- In an engine model with a front-end accessory drive (FEAD)
- To model engine start and stop scenarios

The Starter block supports only an angular speed input to the DC motor. A load torque input requires engine dynamics.

Separately Excited DC Motor

In a separately excited DC motor, the field winding is connected to a separate source of DC power.

The relationship between the field winding voltage, field resistance, and field inductance is given by:

$$V_f = L_f \frac{di_f}{dt} + R_f i_f$$

The counter-electromotive force is a product of the field resistance, mutual inductance, and motor shaft angular speed:

$$EMF = L_a i_f L_{af} \omega$$

The armature voltage is given by:

$$V_a = L_a \frac{di_a}{dt} + R_a i_a + EMF$$

The starter motor current load is the sum of the field winding current and armature winding current:

$$i_{load} = i_f + i_a$$

The starter motor shaft torque is the product of the armature current, field current, and mutual inductance:

$$T_{mech} = i_a i_f L_{af}$$

Permanent Magnet DC Motor

In a permanent magnet DC motor, the magnets establish the excitation flux, so there is no field current.

The counter-electromotive force is proportional to the motor shaft angular speed:

$$EMF = K_t\omega$$

The armature voltage is given by:

$$V_a = L_a \frac{di_a}{dt} + R_a i_a + EMF$$

The starter motor current load is equal to the armature winding current:

$$i_{load} = i_a$$

The starter motor shaft torque is proportional to the armature winding current:

$$T_{mech} = K_t i_a$$

Series Excited DC Motor

A series excited DC motor connects the armature and field windings in series with a common DC power source.

The counter-electromotive force is a product of the field and armature initial series current, field, and armature mutual inductance and motor shaft angular speed:

$$EMF = i_{af} L_{af} \omega$$

The field and armature winding voltage is given by:

$$V_{af} = L_{ser} \frac{di_{af}}{dt} + R_{ser} i_{af} + EMF$$

The starter motor current load is equal to the field and armature series current:

$$i_{load} = i_{af}$$

The starter motor shaft torque is the product of the squared field and armature series current and the field and armature mutual inductance:

$$T_{mech} = i_{af}^2 L_{af}$$

For motor stability, the motor shaft angular speed must be greater than the ratio of the series connected field and armature resistance to the mutual inductance:

$$\omega > - \frac{R_{ser}}{L_{af}}$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	P_{mot}	$P_{mot} = -\omega T_{mech}$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	P_{bus}	Separately excited DC motor
					PM excited DC motor
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrLoss	Motor losses	P_{loss}	$P_{loss} = -(P_{mot} + P_{bus} - P_{ind})$	
PwrStored	— Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrInd	Electrical inductance	P_{ind}	Separately excited DC motor
					$P_{ind} = L_f i_f \frac{di_f}{dt} + L_a i_a \frac{di_a}{dt}$
					PM excited DC motor
Series excited DC motor					
$P_{ind} = L_{ser} i_{af} \frac{di_{af}}{dt}$					

The equations use these variables.

- R_a Armature winding resistance
- L_a Armature winding inductance
- EMF Counter-electromotive force
- R_f Field winding resistance
- L_f Field winding inductance
- L_{af} Field and armature mutual inductance

i_a	Armature winding current
i_f	Field winding current
K_t	Motor torque constant
ω	Motor shaft angular speed
V_a	Armature winding voltage
V_f	Field winding voltage
V_{af}	Field and armature winding voltage
i_{af}	Field and armature series current
R_{ser}	Series connected field and armature resistance
L_{ser}	Series connected field and armature inductance
i_{load}	Starter motor current load
T_{mech}	Starter motor shaft torque

Ports

Inputs

MtrSpd – Angular speed

scalar

Motor shaft angular speed, in rad/s.

StartVOLT – Armature and field voltage

scalar

- Armature winding voltage V_a and field winding voltage V_f in V.
- In series excited DC motor, armature and field winding voltage V_{af} .

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
ArmCurr		Armature winding current	A	
FldCurr		Field winding current	A	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	W
		PwrBus	Electrical power	W
	PwrNotTrnsfrd	PwrLoss	Motor power loss	W
	PwrStored	PwrInd	Electrical inductance	W

LdCurr – Starter motor load current

scalar

Starter motor load current, in A.

MtrTrq – Starter motor shaft torque
 scalar

Starter motor shaft torque, in N·m.

Parameters

Configuration

Motor Type – Select motor type

Separately Excited DC Motor (default) | Permanent Magnet Excited DC Motor | Series Connection DC Motor

Select one of the three motor types.

Dependencies

The table summarizes the motor parameter dependencies.

Motor Type	Enables Motor Parameter
Separately Excited DC Motor	Armature winding resistance, Ra
	Armature winding inductance, La
	Field winding resistance Rf
	Field winding inductance, Lf
	Mutual inductance, Laf
Permanent Magnet Excited DC Motor	Initial armature and field current, Iaf
	Armature winding resistance, Rapm
	Armature winding inductance, Lapm
	Torque constant, Kt
Series Connection DC Motor	Initial armature current, Ia
	Total resistance, Rser
	Total inductance, Lser
	Initial current, Iafser
	Mutual inductance, Lafser

Separately Excited DC Motor

Armature winding resistance, Ra – Resistance
 1 (default) | scalar

Armature winding resistance, in ohm.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Armature winding inductance, La – Inductance
 .1 (default) | scalar

Armature winding inductance, in H.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Field winding resistance, R_f – Resistance

.3 (default) | scalar

Field winding resistance, in ohm.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Field winding inductance, L_f – Inductance

.2 (default) | scalar

Field winding inductance, in H.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Mutual inductance, L_{af} – Inductance

.3 (default) | scalar

Mutual inductance, in H.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Initial armature current and field current, I_{af} – Current

[0 0] (default) | vector

Initial armature and field current, in A.

Dependencies

To enable this parameter, select Separately Excited DC Motor for the **Motor Type** parameter.

Permanent Magnet Excited DC Motor

Armature winding resistance, R_{apm} – Resistance

.5 (default) | scalar

Armature winding resistance, in ohm.

Dependencies

To enable this parameter, select Permanent Magnet Excited DC Motor for the **Motor Type** parameter.

Armature winding inductance, L_{apm} – Inductance

.1 (default) | scalar

Armature winding inductance, in H.

Dependencies

To enable this parameter, select Permanent Magnet Excited DC Motor for the **Motor Type** parameter.

Torque constant, K_t — Motor torque constant

.1 (default) | scalar

Motor torque constant, in N·m/A.

Dependencies

To enable this parameter, select Permanent Magnet Excited DC Motor for the **Motor Type** parameter.

Initial armature current, I_a — Current

.1 (default) | scalar

Initial armature current, in A.

Dependencies

To enable this parameter, select Permanent Magnet Excited DC Motor for the **Motor Type** parameter.

Series Connection DC Motor**Total resistance, R_{ser} — Resistance**

.1 (default) | scalar

Series connected field and armature resistance, in ohm.

Dependencies

To enable this parameter, select Series Excited DC Motor for the **Motor Type** parameter.

Total inductance, L_{ser} — Inductance

.1 (default) | scalar

Series connected field and armature inductance, in H.

Dependencies

To enable this parameter, select Series Excited DC Motor for the **Motor Type** parameter.

Initial current, I_{afser} — Current

0 (default) | scalar

Initial series current, in A.

Dependencies

To enable this parameter, select Series Excited DC Motor for the **Motor Type** parameter.

Mutual inductance, L_{afser} — Inductance

.3 (default) | scalar

Field and armature mutual inductance, in H.

Dependencies

To enable this parameter, select `Series Excited DC Motor` for the **Motor Type** parameter.

Version History

Introduced in R2017a

References

[1] Krause, P. C. *Analysis of Electric Machinery*. New York: McGraw-Hill, 1994.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

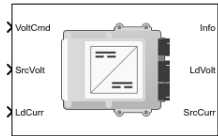
See Also

Reduced Lundell Alternator

Bidirectional DC-DC

DC-to-DC converter that supports bidirectional boost and buck

Library: Powertrain Blockset / Energy Storage and Auxiliary Drive / DC-DC



Description

The Bidirectional DC-DC block implements a DC-to-DC converter that supports bidirectional boost and buck (lower) operation. Unless the DC-to-DC conversion limits the power, the output voltage tracks the voltage command. You can specify electrical losses or measured efficiency.

Depending on your battery system configuration, the voltage might not be at a potential that is required by electrical system components such as inverters and motors. You can use the block to boost or buck the voltage. Connect the block to the battery and one of these blocks:

- Mapped Motor
- IM Controller
- Interior PM Controller
- Surface Mount PM Controller

To calculate the electrical loss during the DC-to-DC conversion, use **Parameterize losses by**.

Parameter Option	Description
Single efficiency measurement	Electrical loss calculated using a constant value for conversion efficiency.
Tabulated loss data	Electrical loss calculated as a function of load current and voltage. DC-to-DC converter data sheets typically provide loss data in this format. When you use this option, provide data for all the operating quadrants in which the simulation will run. If you provide partial data, the block assumes the same loss pattern for other quadrants. The block does not extrapolate loss that is outside the range voltage and current that you provide. The block allows you to account for fixed losses that are still present for zero voltage or current.

Parameter Option	Description
Tabulated efficiency data	<p>Electrical loss calculated using conversion efficiency that is a function of load current and voltage. When you use this option, provide data for all the operating quadrants in which the simulation will run. If you provide partial data, the block assumes the same efficiency pattern for other quadrants. The block:</p> <ul style="list-style-type: none"> Assumes zero loss when either the voltage or current is zero. Uses linear interpolation to determine the loss. At lower power conditions, for calculation accuracy, provide efficiency at low voltage and low current.

Note The block does not support inversion. The polarity of the input voltage matches the polarity of the output voltage.

Theory

The Bidirectional DC-DC block uses the commanded voltage and the actual voltage to determine whether to boost or buck (lower) the voltage. You can specify a time constant for the voltage response.

If	Then
$Volt_{cmd} > Src_{Volt}$	Boost
$Volt_{cmd} < Src_{Volt}$	Buck

The Bidirectional DC-DC block uses a time constant-based regulator to provide a fixed output voltage that is independent of load current. Using the output voltage and current, the block determines the losses of the DC-to-DC conversion. The block uses the conversion losses to calculate the input current. The block accounts for:

- Bidirectional current flow
 - Source to load — Battery discharge
 - Load to source — Battery charge
- Rated power limits

The block provides voltage control that is power limited based on these equations. The voltage is fixed. The block does not implement a voltage drop because the load current approximates DC-to-DC conversion with a bandwidth that is greater than the load current draw.

DC-to-DC converter load voltage	$LdVolt_{Cmd} = \min(Volt_{Cmd}, \frac{P_{limit}}{Ld_{Amp}}, 0)$ $LdVolt = LdVolt_{Cmd} \cdot \frac{1}{TS + 1}$
Power loss for single efficiency source to load	$P_{Wr_{Loss}} = \frac{100 - Eff}{Eff} \cdot Ld_{Volt} \cdot Ld_{Amp}$

Power loss for single efficiency load to source	$P_{WrLoss} = \frac{100 - Eff}{Eff} \cdot Ld_{Volt} \cdot Ld_{Amp} $
Power loss for tabulated efficiency	$Prw_{Loss} = f(Ld_{Volt}, Ld_{Amp})$
Source current draw from DC-to-DC converter	$Src_{Amp} = \frac{Ld_{Pwr} + Prw_{Loss}}{Src_{Volt}}$
Source power from DC-to-DC converter	$Src_{Pwr} = Src_{Amp} \cdot Src_{Volt}$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrBusSrc	Source power to DC-to-DC converter	$P_{src} = Src_{Pwr}$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBusLd	Load power from DC-to-DC converter	$P_{bus} = -Ld_{Volt}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrLoss	Converter power loss	$P_{loss} = Pwr_{Loss}$
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 			
	PwrStored — Stored energy rate of change		Not used	
	<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 			

The equations use these variables.

$Volt_{Cmd}$	DC-to-DC converter commanded output voltage
Src_{Volt}	Source input voltage to DC-to-DC converter
Ld_{Amp}	Load current of DC-to-DC converter
Ld_{Volt}	Load voltage of DC-to-DC converter
Src_{Amp}	Source current draw from DC-to-DC converter
τ	Conversion time constant
V_{init}	Initial load voltage of the DC-to-DC converter
P_{limit}	Output power limit for DC-to-DC converter
Eff	Input to output efficiency
Src_{Pwr}	Source power to DC-to-DC converter
Ld_{Pwr}	Load power from DC-to-DC converter

Pwr_{Loss} Power loss
 $LdVolt_{Cmd}$ Commanded load voltage of DC-to-DC converter before application of time constant

Ports

Inputs

VoltCmd — Commanded voltage

scalar

DC-to-DC converter commanded output voltage, $Volt_{Cmd}$, in V.

SrcVolt — Input voltage

scalar

Source input voltage to DC-to-DC converter, Src_{Volt} , in V.

LdCurr — Load current

scalar

Load current of DC-to-DC converter, Ld_{Amp} , in A.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
SrcPwr		Source power to DC-to-DC converter	Src_{Pwr}	W	
LdPwr		Load power from DC-to-DC converter	Ld_{Pwr}	W	
PwrLoss		Power loss	Pwr_{Loss}	W	
LdVoltCmd		Commanded load voltage of DC-to-DC converter before application of time constant	$LdVolt_{Cmd}$	V	
PwrInfo	PwrTrnsfrd	PwrBusSrc	Source power to DC-to-DC converter	P_{src}	W
		PwrBusLd	Load power from DC-to-DC converter	P_{bus}	W
	PwrNotTrnsfrd	PwrLoss	Converter power loss	P_{loss}	W
	PwrStored	<i>Not used</i>			

LdVolt — Load voltage

scalar

Load voltage of DC-to-DC converter, Ld_{Volt} , in V.

SrcCurr – Source current

scalar

Source current draw from DC-to-DC converter, Src_{Amp} , in A.**Parameters****Electrical Control****Converter response time constant – Constant**

1/1000 (default) | scalar

Converter response time, τ , in s.**Converter response initial voltage, Vinit – Voltage**

0 (default) | scalar

Initial load voltage of the DC-to-DC converter, V_{init} , in V.**Converter power limit, Plimit – Power**

100000 (default) | scalar

Initial load voltage of the DC-to-DC converter, P_{limit} , in W.**Electrical Losses****Parameterize losses by – Loss calculation**

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

This table summarizes the loss options used to calculate electrical options.

Parameter Option	Description
Single efficiency measurement	Electrical loss calculated using a constant value for conversion efficiency.
Tabulated loss data	Electrical loss calculated as a function of load current and voltage. DC-to-DC converter data sheets typically provide loss data in this format. When you use this option, provide data for all the operating quadrants in which the simulation will run. If you provide partial data, the block assumes the same loss pattern for other quadrants. The block does not extrapolate loss that is outside the range voltage and current that you provide. The block allows you to account for fixed losses that are still present for zero voltage or current.

Parameter Option	Description
Tabulated efficiency data	<p>Electrical loss calculated using conversion efficiency that is a function of load current and voltage. When you use this option, provide data for all the operating quadrants in which the simulation will run. If you provide partial data, the block assumes the same efficiency pattern for other quadrants. The block:</p> <ul style="list-style-type: none"> Assumes zero loss when either the voltage or current is zero. Uses linear interpolation to determine the loss. At lower power conditions, for calculation accuracy, provide efficiency at low voltage and low current.

Overall DC to DC converter efficiency, *eff* – Constant

98 (default) | scalar

Overall conversion efficiency, *Eff*, in %.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Single efficiency measurement.

Vector of voltages (*v*) for tabulated loss, *v_loss_bp* – Breakpoints

[0 200 400 600 800 1000] (default) | 1-by-M vector

Tabulated loss breakpoints for M load voltages, in V.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of currents (*i*) for tabulated loss, *i_loss_bp* – Breakpoints

[0 25 50 75 100] (default) | 1-by-N vector

Tabulated loss breakpoints for N load currents, in A.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Corresponding losses, *losses_table* – 2-D lookup table

N-by-M matrix

Electrical loss map, as a function of N load currents and M load voltages, in W.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of voltages (*v*) for tabulated efficiency, *v_eff_bp* – Breakpoints

[200 400 600 800 1000] (default) | 1-by-M vector

Tabulated efficiency breakpoints for M load voltages, in V.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Vector of currents (i) for tabulated efficiency, i_eff_bp – Breakpoints

[25 50 75 100] (default) | 1-by-N vector

Tabulated efficiency breakpoints for N load currents, in A.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Corresponding efficiency, efficiency_table – 2-D lookup table

N-by-M matrix

Electrical efficiency map, as a function of N load currents and M load voltages, in %.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Version History

Introduced in R2017b

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Estimation Equivalent Circuit Battery | Equivalent Circuit Battery

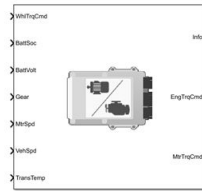
Topics

Battery Modeling

Equivalent Consumption Minimization Strategy

Energy management controller for P0-P4 hybrid electric vehicles

Library: Powertrain Blockset / Propulsion / Supervisory Controllers

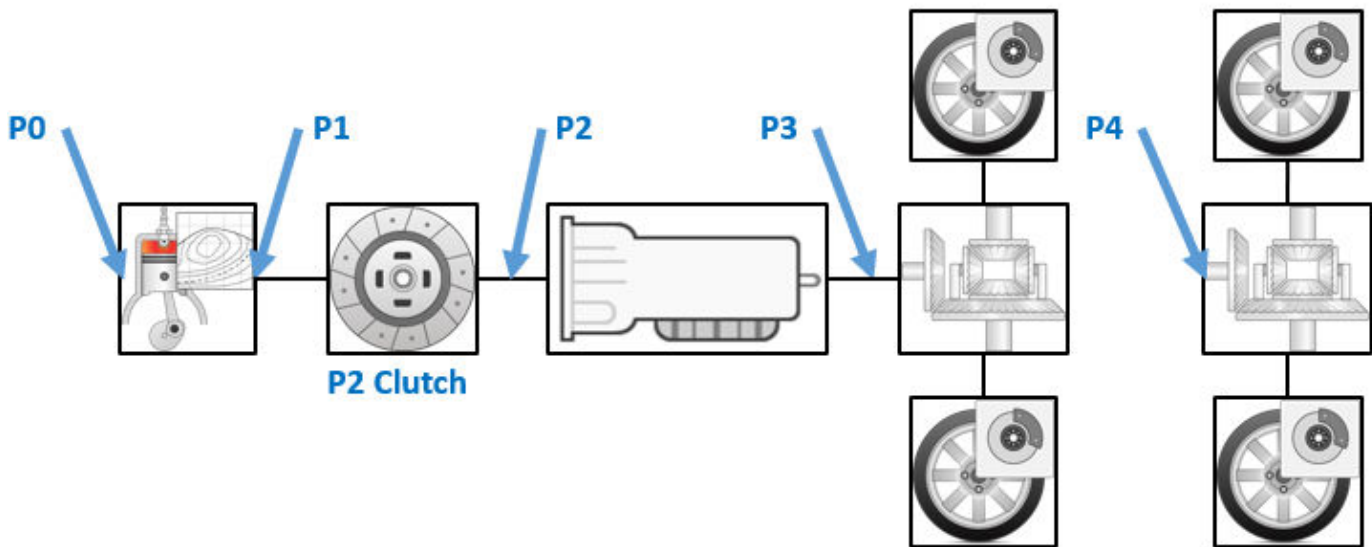


Description

Use the Equivalent Consumption Minimization Strategy (ECMS) block to control the energy management of hybrid electric vehicles (HEVs). The block optimizes the torque split between the engine and motor to minimize energy consumption while maintaining the battery state of charge (SOC).

The HEV P0, P1, P2, P3, and P4 reference applications use the Equivalent Consumption Minimization Strategy block for hybrid control.

Use the **Motor location** parameter to specify the HEV motor location.



Use the **ECMS method** parameter to implement either an adaptive or non-adaptive ECMS method. The HEV architectures are charge-sustaining, meaning the battery SOC must remain in a specified range because there is no plugin capability to recharge the battery. The battery is an energy buffer, and all energy comes from the fuel if the change in SOC is minimized over a drive cycle. To sustain the charge over a specified drive cycle, the block implements either of these ECMS methods.

ECMS Method	Description
Non-adaptive (default)	<p>The block uses a constant ECMS equivalence factor.</p> <ul style="list-style-type: none"> • Use this method to determine the best fuel economy over a drive cycle. <ul style="list-style-type: none"> • If you change the drive cycle or HEV architecture, retune the ECMS weighting factor to maintain the ending SOC. • By default, the block uses a single constant.
Adaptive	<p>The block adjusts an ECMS equivalence factor by using the output of a PI controller.</p> <ul style="list-style-type: none"> • Use this method to maintain the SOC and minimize the delta SOC over many drive cycles. The block: <ul style="list-style-type: none"> • Tunes the PI controller gains. • Sustains the SOC. • The PI controller minimizes the error between the target SOC and current SOC.

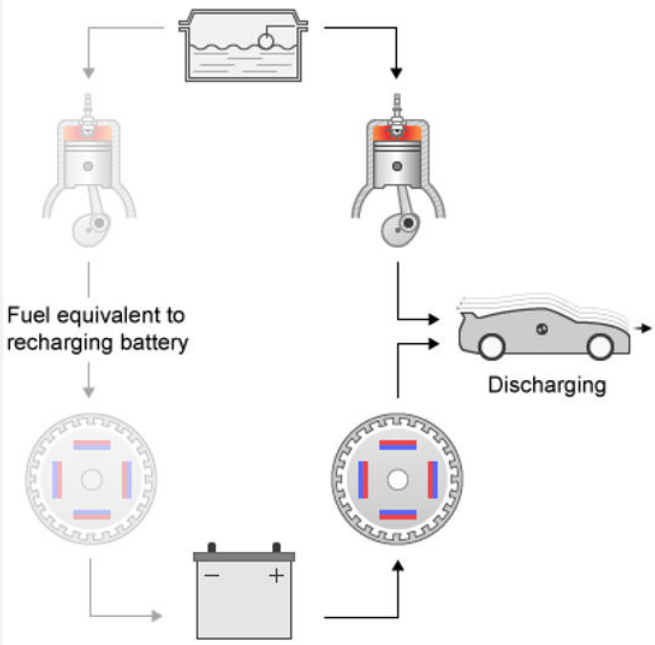
ECMS Control Algorithm

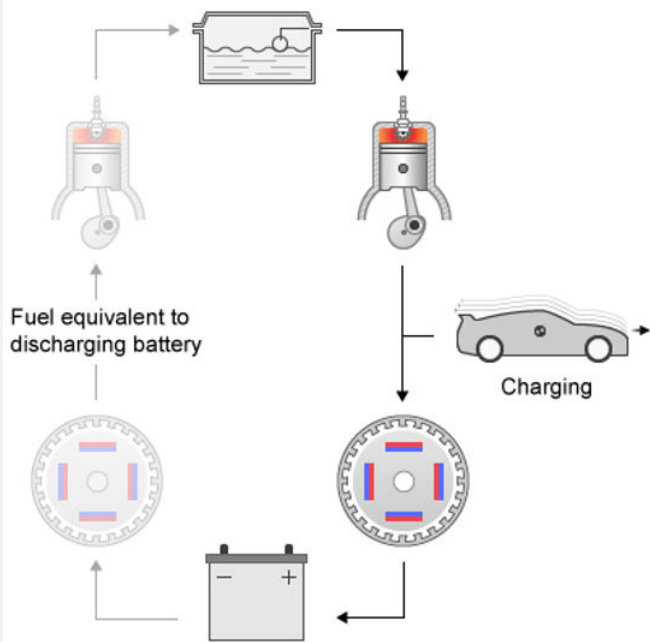
The block implements a dynamic supervisory controller that determines the engine torque, motor torque, starter, clutch, and brake pressure commands. Specifically, the block:

- Converts the driver accelerator pedal signal to a wheel torque request. To calculate the total powertrain torque at the wheels, the algorithm uses the maximum engine torque and motor torque curves and the transmission and differential gear ratios.
- Converts the driver brake pedal signal to a brake pressure request. The algorithm multiplies the brake pedal signal by a maximum brake pressure.
- Implements a regenerative braking algorithm for the traction motor to recover the maximum amount of kinetic energy from the vehicle.

The block implements an ECMS algorithm^[2] that optimizes the torque split between the engine and motor to minimize energy consumption while maintaining the battery SOC. Specifically, the ECMS:

- Assigns a cost to electrical energy, so that using stored electrical energy is equal to consuming fuel energy.

Battery Mode	Equivalent Electrical Energy	Description
Discharging	Positive	<p>Battery discharges stored electrical energy when the electric machine is in use.</p> 

Battery Mode	Equivalent Electrical Energy	Description
Charging	Negative	<p>Battery stores electrical energy from either the:</p> <ul style="list-style-type: none"> • Engine and electric machine acting as a generator • Electric machine acting as a generator during regenerative braking 

- Is an instantaneous minimization method that the software solves at every controller time step. To implement the strategy, the ECMS selects the optimal motor and engine torque in the optimization strategy to minimize the equivalent energy consumption.
- Implements either an adaptive or non-adaptive ECMS method.

Ports

Input

WhlTrqCmd – Wheel torque command
scalar

Wheel torque command.

Data Types: double

BattSoc – Battery state of charge
scalar

Battery state of charge.

Data Types: double

BattVolt — Battery voltage

scalar

Battery voltage.

Data Types: double

Gear — Transmission gear

scalar

Transmission gear.

Data Types: double

MtrSpd — Motor speed

scalar

Motor speed.

Data Types: double

VehSpd — Vehicle speed

scalar

Vehicle speed, in m/s.

Data Types: double

TransTemp — Transmission temperature

scalar

Transmission temperature, in K.

Data Types: double

Output

Info — Block data

bus

Block data, returned as a bus signal that contains these block values.

Signal	Description	Units
EngTrqCmd	Engine torque command	N·m
MtrTrqCmd	Motor torque command	N·m
EquivFctr	Equivalence factor	NA
MinHamil	Minimum Hamiltonian	kW

EngTrqCmd — Engine torque command

scalar

Engine torque command, in N·m.

Data Types: double

MtrTrqCmd — Motor torque command

scalar

Motor torque command, in N·m.

Data Types: double

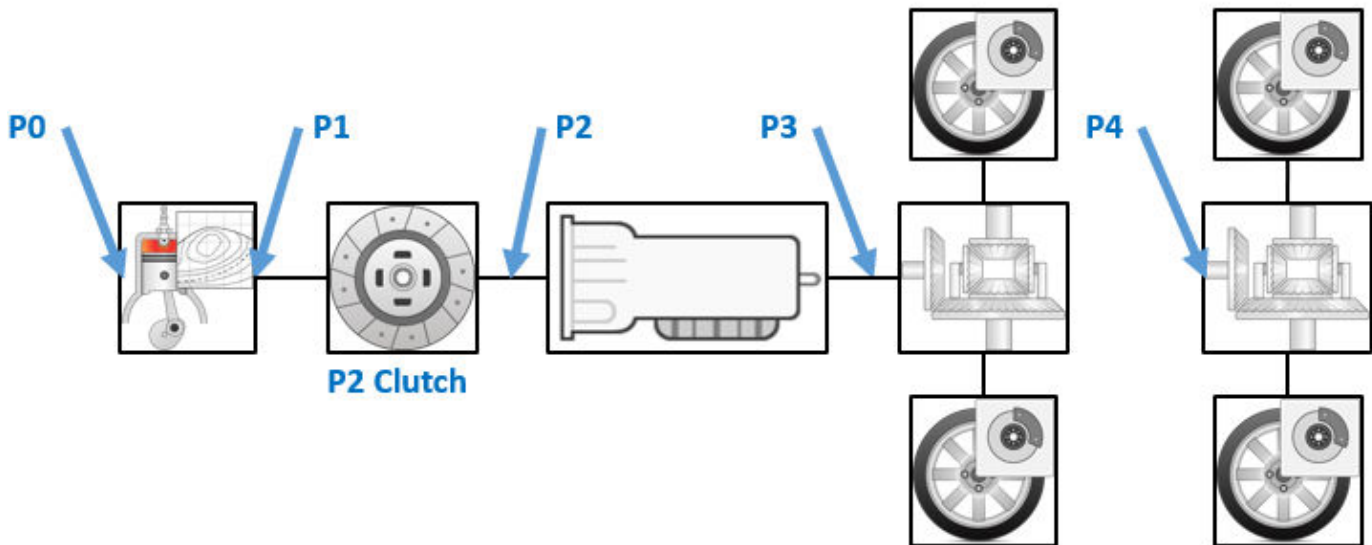
Parameters

Block Options

Motor location – Location of motor

P0 (default) | P1 | P2 | P3 | P4

Specify the HEV motor location.



ECMS method – ECMS method

Non-adaptive (default) | Adaptive

Use the **ECMS method** parameter to implement either an adaptive or non-adaptive ECMS method. The HEV architectures are charge-sustaining, meaning the battery SOC must remain in a specified range because there is no plugin capability to recharge the battery. The battery is an energy buffer, and all energy comes from the fuel if the change in SOC is minimized over a drive cycle. To sustain the charge over a specified drive cycle, the block implements either of these ECMS methods.

ECMS Method	Description
Non-adaptive (default)	<p>The block uses a constant ECMS equivalence factor.</p> <ul style="list-style-type: none"> Use this method to determine the best fuel economy over a drive cycle. <ul style="list-style-type: none"> If you change the drive cycle or HEV architecture, retune the ECMS weighting factor to maintain the ending SOC. By default, the block uses a single constant.

ECMS Method	Description
Adaptive	<p>The block adjusts an ECMS equivalence factor by using the output of a PI controller.</p> <ul style="list-style-type: none"> Use this method to maintain the SOC and minimize the delta SOC over many drive cycles. The block: <ul style="list-style-type: none"> Tunes the PI controller gains. Sustains the SOC. The PI controller minimizes the error between the target SOC and current SOC.

Differential

Differential gear ratio, N_diff – Differential gear ratio

3.32 (default) | scalar

Differential gear ratio. No dimension.

Data Types: double

Differential efficiency factor, eta_diff – Differential efficiency factor

0.98 (default) | scalar

Differential efficiency factor. No dimension.

Data Types: double

Loaded wheel radius, Re – Loaded wheel radius

0.327 (default) | scalar

Loaded wheel radius, in m.

Data Types: double

Transmission

Transmission efficiency factors – Transmission efficiency factors

Gear, input torque, input speed, and temperature (default) | Gear only

Transmission efficiency factors.

Data Types: double

Transmission gear number vector, G_trans – Transmission gear number vector

[0 1 2 3 4 5 6] (default) | vector

Transmission gear number vector. No dimension.

Data Types: double

Transmission gear ratio vector, N_trans – Transmission gear ratio vector

[1 4.212 2.637 1.8 1.386 1 0.772] (default) | vector

Transmission gear ratio vector. No dimension.

Data Types: double

Transmission efficiency vector, eta_trans – Transmission efficiency vector

[1 1 1 1 1 1 1] (default) | vector

Transmission efficiency vector. No dimension.

DependenciesTo enable this parameter, set **Transmission efficiency factors** to Gear only.

Data Types: double

Transmission efficiency torque breakpoints, Trq_trans_bpts – Transmission efficiency torque breakpoints

[25 50 75 100 150 200 250] (default) | vector

Transmission efficiency torque breakpoints, in N·m.

DependenciesTo enable this parameter, set **Transmission efficiency factors** to Gear, input torque, input speed, and temperature.

Data Types: double

Transmission efficiency speed breakpoints, omega_trans_bpts – Transmission efficiency speed breakpoints[500.383141080919 749.619781962827 1002.676141478941 1250.957852702297
1499.239563925654 1747.521275149011 1995.802986372368 2501.915705404595
2998.479127851308 4001.155269330249 5003.83141080919] (default) | vector

Transmission efficiency speed breakpoints, in rad/s.

DependenciesTo enable this parameter, set **Transmission efficiency factors** to Gear, input torque, input speed, and temperature.

Data Types: double

Transmission efficiency temperature breakpoints, Temp_trans_bpts – Transmission efficiency temperature breakpoints

[313 358] (default) | vector

Transmission efficiency temperature breakpoints, in K.

DependenciesTo enable this parameter, set **Transmission efficiency factors** to Gear, input torque, input speed, and temperature.

Data Types: double

Transmission efficiency vector, eta_trans_tbl – Transmission efficiency vector

array

Transmission efficiency vector. No dimension.

Dependencies

To enable this parameter, set **Transmission efficiency factors** to Gear, input torque, input speed, and temperature.

Data Types: double

Engine**Speed breakpoints, f_tbrake_n_bpt — Speed breakpoints**

[0 750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default) | vector

Speed breakpoints, in rpm.

Data Types: double

Commanded torque breakpoints, f_tbrake_t_bpt — Commanded torque breakpoints

[0 15 26.4285714285714 37.8571428571429 49.2857142857143 60.7142857142857 72.1428571428571 83.5714285714286 95 106.428571428571 117.857142857143 129.285714285714 140.714285714286 152.142857142857 163.571428571429 175] (default) | vector

Commanded torque breakpoints, in N·m.

Data Types: double

Brake torque map, f_tbrake — Brake torque map

array

Brake torque map, in N·m.

Data Types: double

Minimum engine torque command table, f_tbrake_min — Minimum engine torque command table

vector

Minimum engine torque command table, in N·m.

Data Types: double

Fuel flow map, f_fuel — Fuel flow map

array

Fuel flow map, in kg/s.

Data Types: double

Minimum engine torque command, HEVEngTrq_min — Minimum engine torque command

16.18610438796213 (default) | scalar

Minimum engine torque command, in N·m.

Data Types: double

Fuel lower heating value, LHV – Fuel lower heating value

46000000 (default) | scalar

Fuel lower heating value, in J/kg.

Data Types: double

Engine idle speed, N_idle – Engine idle speed

750 (default) | scalar

Engine idle speed, in rpm.

Data Types: double

Battery**Battery state-of-charge breakpoints, SOC_bpt – Battery state-of-charge breakpoints**

[0 0.1 0.2 0.3 0.4 0.5 0.6 0.7 0.8 0.9 1] (default) | vector

Battery state-of-charge breakpoints. No dimension.

Data Types: double

Battery charge limit table, ChrgLmt – Battery charge limit table

[1 1 1 1 1 1 1 0.9 0.7 0.5 0] (default) | vector

Battery charge limit table. No dimension.

Data Types: double

Battery discharge limit table, DischrgLmt – Battery discharge limit table

[0 0.5 0.7 0.9 1 1 1 1 1 1 1] (default) | vector

Battery discharge limit table. No dimension.

Data Types: double

Maximum battery current, BattCurrMax – Maximum battery current

150 (default) | scalar

Maximum battery current, in A.

Data Types: double

DC/DC converter efficiency, eta_dcdc – DC/DC converter efficiency

1 (default) | scalar

DC/DC converter efficiency. No dimension.

Data Types: double

Maximum battery charge power, BattChrgPwrMax – Maximum battery charge power

-30000 (default) | scalar

Maximum battery charge power, in W.

Data Types: double

Maximum battery discharge power, BattDischrgPwrMax — Maximum battery discharge power

46000 (default) | scalar

Maximum battery discharge power, in W.

Data Types: double

Motor

Motor maximum torque table, f_tmtr_max — Motor maximum torque table
vector

Motor maximum torque table, in N·m.

Data Types: double

Motor speed breakpoints, f_mtr_w_bpt — Motor speed breakpoints
vector

Motor speed breakpoints, in rpm.

Data Types: double

Motor torque breakpoints, f_mtr_t_bpt — Motor torque breakpoints
vector

Motor torque breakpoints, in N·m.

Data Types: double

Motor efficiency map, f_mtr_eta — Motor efficiency map
array

Motor efficiency map. No dimension.

Data Types: double

Number of motor torque calculation points, Ngrid — Number of motor torque calculation points

200 (default) | scalar

Number of motor torque calculation points. No dimension.

Data Types: double

P0 belt ratio, N_P0 — P0 belt ratio

3 (default) | scalar

P0 belt ratio. No dimension.

Dependencies

To enable this parameter, set **Motor location** to P0.

Data Types: double

Energy Management**ECMS weighting factor, ECMS_s — ECMS weighting factor**

3.385 (default) | scalar

ECMS weighting factor. No dimension.

Data Types: double

Penalty factor power, PenaltyFctrPwr — Penalty factor power

3 (default) | scalar

Penalty factor power. No dimension.

Data Types: double

Adaptive ECMS proportional gain, ECMS_Kp — Adaptive ECMS proportional gain

0 (default) | scalar

Adaptive ECMS proportional gain. No dimension.

DependenciesTo enable this parameter, set **ECMS method** to Adaptive.

Data Types: double

Adaptive ECMS integral gain, ECMS_Ki — Adaptive ECMS integral gain

0 (default) | scalar

Adaptive ECMS integral gain. No dimension.

DependenciesTo enable this parameter, set **ECMS method** to Adaptive.

Data Types: double

Constraint penalty factor, PenaltyFctr — Constraint penalty factor

10000000 (default) | scalar

Constraint penalty factor. No dimension.

Data Types: double

Target battery state-of-charge, SOCTrgt — Target battery state-of-charge

60 (default) | scalar

Target battery state-of-charge. No dimension.

Data Types: double

Minimum battery state-of-charge, SOCmin — Minimum battery state-of-charge

40 (default) | scalar

Minimum battery state-of-charge. No dimension.

Data Types: double

Maximum battery state-of-charge, SOCmax — Maximum battery state-of-charge

80 (default) | scalar

Maximum battery state-of-charge. No dimension.

Data Types: double

Acknowledgments

MathWorks® would like to acknowledge the contribution of Dr. Simona Onori to the ECMS optimal control algorithm implemented in this block. Dr. Onori is a Professor of Energy Resources Engineering at Stanford University. Her research interests include electrochemical modeling, estimation and optimization of energy storage devices for automotive and grid-level applications, hybrid and electric vehicles modeling and control, PDE modeling, and model-order reduction and estimation of emission mitigation systems. She is a senior member of IEEE.

Version History

Introduced in R2020b

References

- [1] Balazs, A., Morra, E., and Pischinger, S., *Optimization of Electrified Powertrains for City Cars*. SAE Technical Paper 2011-01-2451. Warrendale, PA: SAE International Journal of Alternative Powertrains, 2012.
- [2] Onori, S., Serrao, L., and Rizzoni, G., *Hybrid Electric Vehicles Energy Management Systems*. New York: Springer, 2016.

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

See Also**Topics**

“Hybrid and Electric Vehicle Reference Application Projects”

Power Accounting Bus Creator

Create power information bus

Library: Powertrain Blockset / Utilities / Power Accounting



Description

Creates a power information bus for reporting system power and energy consumption. You can associate the block to a parent system, select types of power signals to track, and add signal descriptions. If you want to generate a power and energy report, you must use this block to log the power signals in your plant model blocks. The Powertrain Blockset plant blocks use the Power Accounting Bus Creator to log the power signals. The documentation for each block includes information about the logged power bus signals.

The system-level power and energy accounting satisfies the conservation of energy.

$$\sum P_{trans} + \sum P_{nottrans} = \sum P_{store}$$

To add the Power Accounting Bus Creator to your plant block, follow these steps:

- 1 Add the Power Accounting Bus Creator block to your block.
- 2 Select the types of power signals that you want to log. See “Power Signals” on page 3-53.
- 3 Associate the Power Accounting Bus Creator with a parent subsystem. See “Block Association” on page 3-54.
- 4 Connect the power signals to the Power Accounting Bus Creator.
 - Follow the sign convention.
 - To ensure that your plant block conserves energy, include all power associated with the block.
- 5 In the Power Accounting Bus Creator:
 - On the **Transferred** power tab, specify these parameters:
 - **Associated Port**
 - **Description**
 - On the **Not Transferred** power tab, specify the **Description** parameter:
- 6 In the plant block, connect the transferred power signals to the Power Accounting Bus Creator ports that are specified with the **Associated Port** parameter.

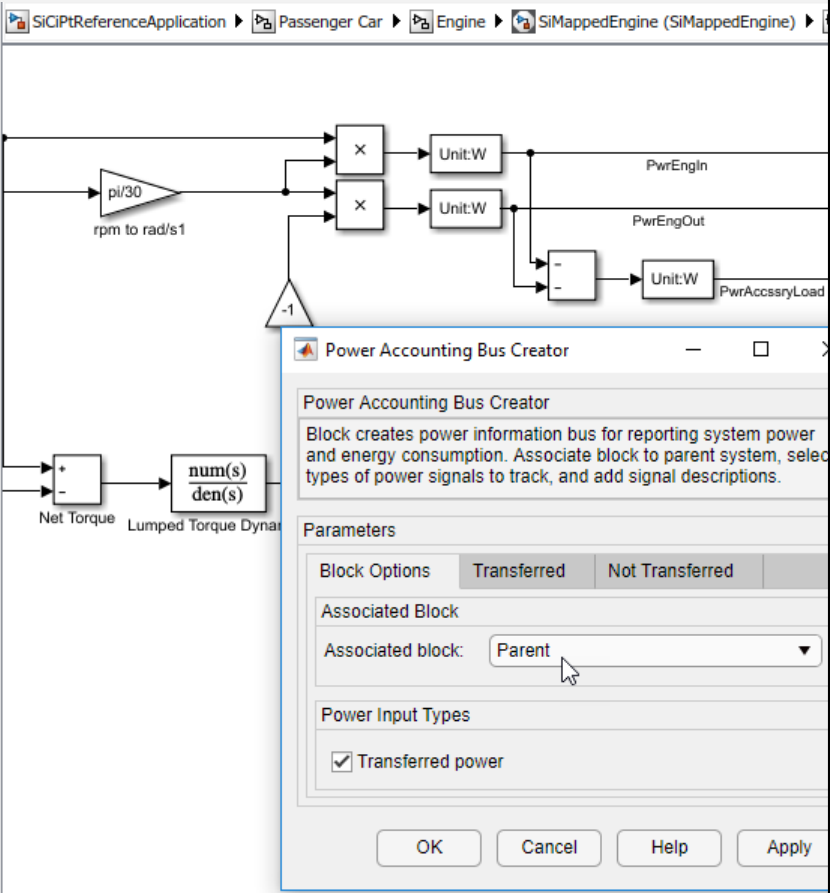
Power Signals

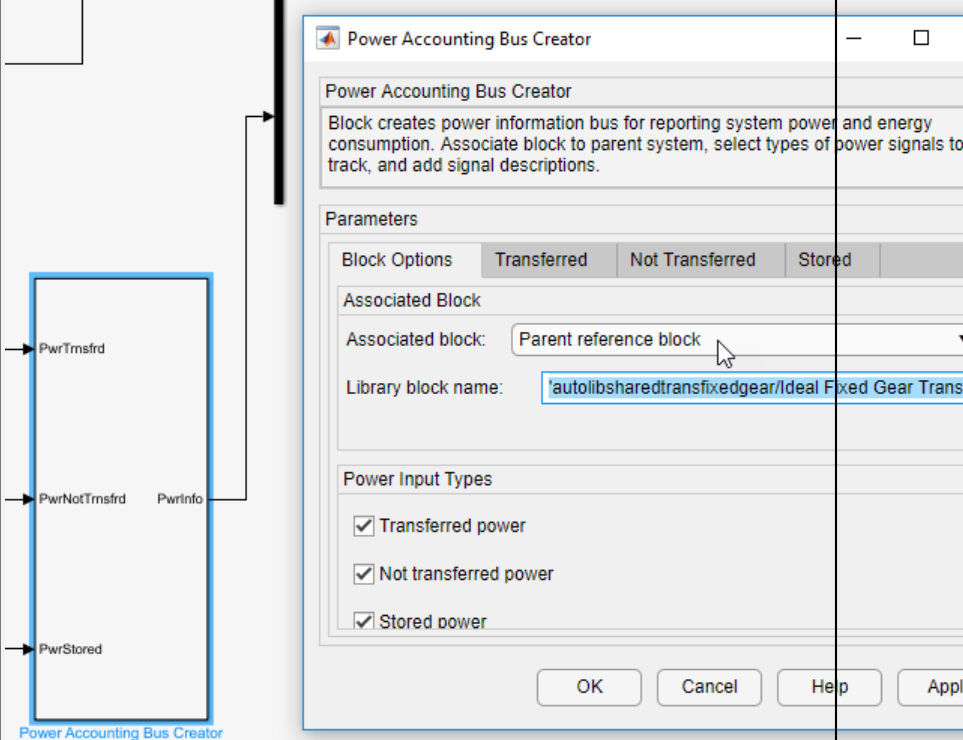
The Power Accounting Bus Creator sorts the signals into three power types.

Power Type		Description	Examples
P_{trans}	Transferred	<p>Power transferred between blocks:</p> <ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	<ul style="list-style-type: none"> • Crankshaft power transferred from mapped engine to transmission. • Road load power transferred from wheel to vehicle. • Rate of heat flow transferred from throttle to manifold volume.
$P_{nottrans}$	Not transferred	<p>Power crossing the block boundary, but not transferred:</p> <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	<ul style="list-style-type: none"> • Rate of heat transfer with the environment. <ul style="list-style-type: none"> • From environment is an input (positive signal) • To environment is a loss (negative signal) • Flow boundary with the environment. <ul style="list-style-type: none"> • From environment is an input (positive signal) • To environment is a loss (negative signal) • Mapped engine fuel flow.
P_{store}	Stored	<p>Stored energy rate of change:</p> <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	<p>Energy rate of change:</p> <ul style="list-style-type: none"> • Battery storage • Kinetic energy in drivetrain components • Vehicle potential energy • Vehicle velocity

Block Association

When you add the Power Accounting Bus Creator to your plant block, you associate the signals to a parent block. There are two association methods.

Method	Description	Example
Parent	<p>Power Accounting Bus Creator associates the power bus signals with the parent block.</p>	<p>In the conventional vehicle reference application, navigate to the Passenger Car > Engine > SiMappedEngine > Accessory Load Model plant subsystem. Open the Power Accounting Bus Creator.</p> <p>The Associated block parameter is set to Parent, so the Power Accounting Bus Creator associates the power signals with the Accessory Load Model plant subsystem.</p> 

Method	Description	Example
<p>Parent reference block</p>	<p>Power Accounting Bus Creator associates the power bus signals with a reference block.</p> <p>Use the Library block name parameter to specify the block.</p>	<p>In the Ideal Fixed Gear Transmission block, navigate to the Bus Creation subsystem. Open the Power Accounting Bus Creator.</p> <p>The Power Accounting Bus Creator block uses these parameter settings to associate the power signals to the Ideal Fixed Gear Transmission block.</p> <ul style="list-style-type: none"> • Associated block parameter is set to Parent reference block. • Library block name parameter is set to 'autolibsharedtransfixedgear/Ideal Fixed Gear Transmission'. 

Ports

Input

PwrTrnsfrd – Power transferred between blocks bus

PwrTrnsfrd – Power transferred between blocks

- Positive signals indicate flow into block
- Negative signals indicate flow out of block

Dependencies

To create this input port, select **Transferred power**.

PwrNotTrnsfrd — Power crossing block boundary, not transferred bus

PwrNotTrnsfrd — Power crossing the block boundary, but not transferred

- Positive signals indicate an input
- Negative signals indicate a loss

Dependencies

To create this input port, select **Not transferred power**.

PwrStored — Stored energy rate of change bus

PwrStored — Stored energy rate of change

- Positive signals indicate an increase
- Negative signals indicate a decrease

Dependencies

To create this input port, select **Stored power**.

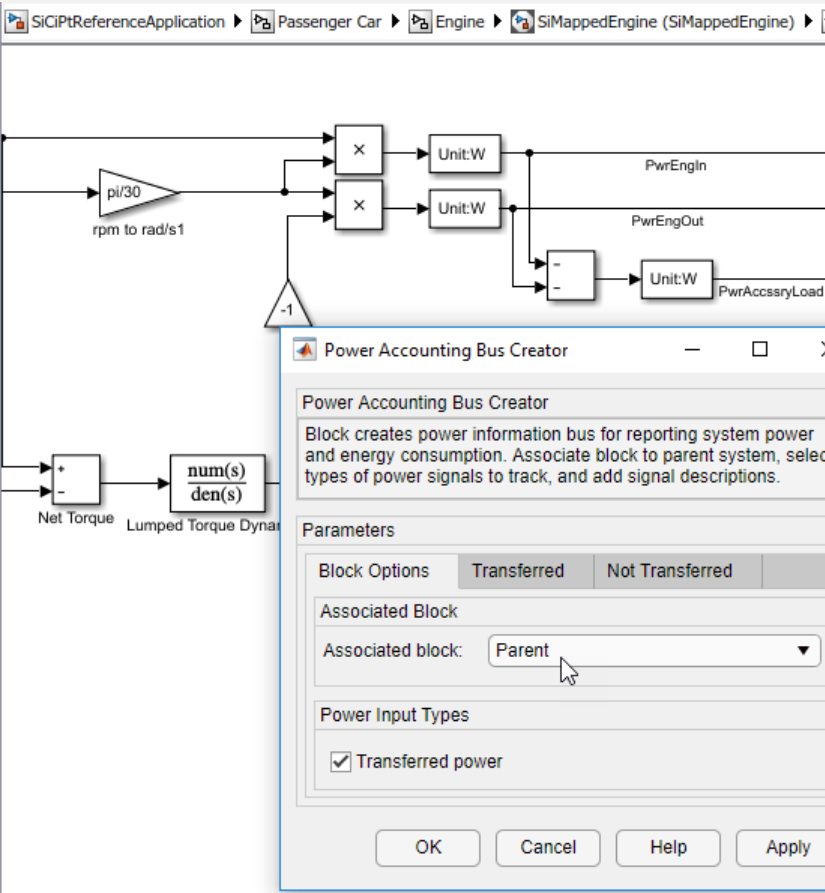
Output**PwrInfo — Power information bus**

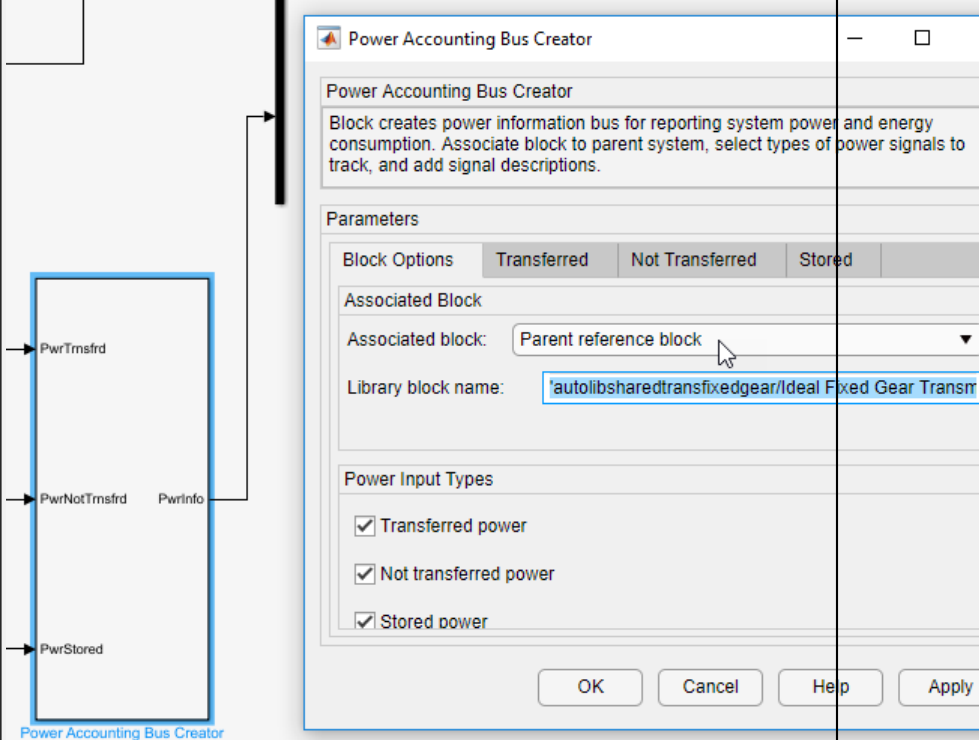
Power information bus

Parameters**Block Options****Associated block — Associated block**

Parent (default) | Parent reference block

When you add the Power Accounting Bus Creator to your plant block, you associate the signals to a parent block. There are two association methods.

Method	Description	Example
Parent	<p>Power Accounting Bus Creator associates the power bus signals with the parent block.</p>	<p>In the conventional vehicle reference application, navigate to the Passenger Car > Engine > SiMappedEngine > Accessory Load Model plant subsystem. Open the Power Accounting Bus Creator.</p> <p>The Associated block parameter is set to Parent, so the Power Accounting Bus Creator associates the power signals with the Accessory Load Model plant subsystem.</p> 

Method	Description	Example
Parent reference block	<p>Power Accounting Bus Creator associates the power bus signals with a reference block.</p> <p>Use the Library block name parameter to specify the block.</p>	<p>In the Ideal Fixed Gear Transmission block, navigate to the Bus Creation subsystem. Open the Power Accounting Bus Creator.</p> <p>The Power Accounting Bus Creator block uses these parameter settings to associate the power signals to the Ideal Fixed Gear Transmission block.</p> <ul style="list-style-type: none"> • Associated block parameter is set to Parent reference block. • Library block name parameter is set to 'autolibsharedtransfixedgear/Ideal Fixed Gear Transmission'. 

Library block name — Block name

Block name

Dependencies

To create this parameter, set **Associated block** to Parent reference block.

Power Input Types

Transferred power — Power transferred between blocks

on (default) | off

Power transferred between blocks.

Dependencies

Selecting this parameter creates the:

- PwrTrnsfrd input port
- **Transferred** parameters

Not transferred power — Power crossing block boundary

on (default) | off

Power crossing block boundary, but not transferred.

Dependencies

Selecting this parameter creates the:

- PwrNotTrnsfrd input port
- **Not Transferred** parameters

Stored power — Stored energy rate of change

on (default) | off

Stored energy rate of change.

Dependencies

Selecting this parameter creates the:

- PwrStored input port
- **Stored** parameters

Transferred

Signal name — Name of signal

char

Signal name.

For example, this table summarizes the Power Accounting Bus Creator parameter **Transferred** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values		
	Signal Name	Associated Port	Description
Ideal Fixed Gear Trans missi on	PwrTrnsfrd.PwrDiffrentl	{'DiffTrq', 'DiffSpd'}	Differential
	PwrTrnsfrd.PwrEng	{'EngTrq', 'EngSpd'}	Engine
Gearb ox	PwrTrnsfrd.PwrBase	{{'BTrq', 'BSpd'}'B'}	Base input
	PwrTrnsfrd.PwrFlwr	{{'FTrq', 'FSpd'}'F'}	Follower output

Block	Power Accounting Bus Creator Parameter Values		
	Signal Name	Associated Port	Description
Boost Drive Shaft	PwrTrnsfrd.PwrCmps	'Cmps'	Compressor
	PwrTrnsfrd.PwrExt	'ExtTrq'	External
	PwrTrnsfrd.Turb	'Turb'	Turbine

Associated Port — Name of ports that transfer power

{'PortA', 'PortB', 'PortC'}

Name of ports that transfer power.

For example, this table summarizes the Power Accounting Bus Creator parameter **Transferred** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values		
	Signal Name	Associated Port	Description
Ideal Fixed Gear Transmission	PwrTrnsfrd.PwrDiffrentl	{'DiffTrq', 'DiffSpd'}	Differential
	PwrTrnsfrd.PwrEng	{'EngTrq', 'EngSpd'}	Engine
Gearbox	PwrTrnsfrd.PwrBase	{{'BTrq', 'BSpd'}'B'}	Base input
	PwrTrnsfrd.PwrFlwr	{{'FTrq', 'FSpd'}'F'}	Follower output
Boost Drive Shaft	PwrTrnsfrd.PwrCmps	'Cmps'	Compressor
	PwrTrnsfrd.PwrExt	'ExtTrq'	External
	PwrTrnsfrd.Turb	'Turb'	Turbine

Description — Signal description

char

Signal description.

For example, this table summarizes the Power Accounting Bus Creator parameter **Transferred** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values		
	Signal Name	Associated Port	Description
Ideal Fixed Gear Transmission	PwrTrnsfrd.PwrDiffrentl	{'DiffTrq', 'DiffSpd'}	Differential
	PwrTrnsfrd.PwrEng	{'EngTrq', 'EngSpd'}	Engine
Gearbox	PwrTrnsfrd.PwrBase	{{'BTrq', 'BSpd'}'B'}	Base input
	PwrTrnsfrd.PwrFlwr	{{'FTrq', 'FSpd'}'F'}	Follower output

Block	Power Accounting Bus Creator Parameter Values		
	Signal Name	Associated Port	Description
Boost Drive Shaft	PwrTrnsfrd.PwrCmps r	'Cmps r'	Compressor
	PwrTrnsfrd.PwrExt	'ExtTrq'	External
	PwrTrnsfrd.Turb	'Turb'	Turbine

Not Transferred

Signal name – Name of signal

char

Signal name.

For example, this table summarizes the Power Accounting Bus Creator parameter **Not Transferred** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values	
	Signal Name	Description
Ideal Fixed Gear Transmission	PwrNotTrnsfrd.PwrDampLoss	Damping loss
	PwrNotTrnsfrd.PwrEffLoss	Efficiency loss
Gearbox	PwrNotTrnsfrd.PwrDampLoss	Damping loss
	PwrNotTrnsfrd.PwrMechLoss	Mechanical loss
Boost Drive Shaft	PwrNotTrnsfrd.PwrMechLoss	Mechanical loss

Description – Signal description

char

Signal description.

For example, this table summarizes the Power Accounting Bus Creator parameter **Not Transferred** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values	
	Signal Name	Description
Ideal Fixed Gear Transmission	PwrNotTrnsfrd.PwrDampLoss	Damping loss
	PwrNotTrnsfrd.PwrEffLoss	Efficiency loss
Gearbox	PwrNotTrnsfrd.PwrDampLoss	Damping loss
	PwrNotTrnsfrd.PwrMechLoss	Mechanical loss
Boost Drive Shaft	PwrNotTrnsfrd.PwrMechLoss	Mechanical loss

Stored**Signal name — Name of signal**

char

Signal name.

For example, this table summarizes the Power Accounting Bus Creator parameter **Stored** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values	
	Signal Name	Description
Ideal Fixed Gear Transmission	PwrStored.PwrStoredTrans	Rotational
Control Volume System	PwrStored.PwrHeatStored	Stored heat
Datasheet Battery	PwrStored.PwrStoredBatt	Battery stored

Description — Signal description

char

Signal description.

For example, this table summarizes the Power Accounting Bus Creator parameter **Stored** parameter values for the listed blocks.

Block	Power Accounting Bus Creator Parameter Values	
	Signal Name	Description
Ideal Fixed Gear Transmission	PwrStored.PwrStoredTrans	Rotational
Control Volume System	PwrStored.PwrHeatStored	Stored heat
Datasheet Battery	PwrStored.PwrStoredBatt	Battery stored

Version History

Introduced in R2019a

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

See Also

autoblks.pwr.PlantInfo

Topics

“Conventional Vehicle Powertrain Efficiency”

“Analyze Power and Energy”

Propulsion Blocks

Boost Drive Shaft

Boost drive shaft speed

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Boost



Description

The Boost Drive Shaft block uses the compressor, turbine, and external torques to calculate the drive shaft speed. Use the block to model turbochargers and superchargers in an engine model.

You can specify these configurations:

- Turbocharger — Connect the compressor to the turbine
 - Two-way ports for turbine and compressor connections
 - Option to add an externally applied input torque
- Compressor only — Connect the drive shaft to the compressor
 - Two-way port for compressor connection
 - Externally applied input torque
- Turbine only — Connect the drive shaft to the turbine
 - Two-way port for turbine connection
 - Externally applied load torque

For the Turbine only and Turbocharger configurations, the block modifies the turbine torque with a mechanical efficiency.

Equations

The Boost Drive Shaft block applies Newton's Second Law for Rotation. Positive torques cause the drive shaft to accelerate. Negative torques impose a load and decelerate the drive shaft.

The block also calculates the power loss due to mechanical inefficiency.

Calculation	Equations
Shaft dynamics	$\frac{d\omega}{dt} = \frac{1}{J_{shaft}}(\eta_{mech}\tau_{turb} + \tau_{comp} + \tau_{ext})$ with initial speed ω_0
Speed constraint	$\omega_{min} \leq \omega \leq \omega_{max}$
Power loss	$\dot{W}_{loss} = \omega\tau_{turb}(1 - \eta_{mech})$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrCmprsr	Shaft power from compressor	$\tau_{comp}\omega$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrTurb	Shaft power from turbine	$\tau_{turb}\omega$
		PwrExt	Externally applied power	$\tau_{ext}\omega$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrMechLoss	Mechanical power loss	$-\dot{W}_{turb}$
<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrStored — Stored energy rate of change	PwrStoredDriveshaft	Rate change in rotational kinetic energy	$(\eta_{mech}\tau_{turb} + \tau_{comp} + \tau_{ext})\omega$

The equations use these variables.

ω	Shaft speed
ω_0	Initial drive shaft speed
ω_{min}	Minimum drive shaft speed
ω_{max}	Maximum drive shaft speed
J_{shaft}	Shaft inertia
η_{max}	Mechanical efficiency of turbine
τ_{comp}	Compressor torque
τ_{turb}	Turbine torque
τ_{ext}	Externally applied torque.
\dot{W}_{loss}	Power loss due to mechanical inefficiency

Ports

Input

Cmprsr — Compressor torque

two-way connector port

Compressor torque, τ_{comp} , in N·m.

Dependencies

To create this port, for the **Configuration** parameter, select Turbocharger or Compressor only.

Turb – Turbine torque

two-way connector port

Turbine torque, τ_{turb} , in N·m.

Dependencies

To create this port, for the **Configuration** parameter, select Turbocharger or Turbine only.

ExtTrq – Externally applied torque

scalar

Externally applied torque, τ_{ext} , in N·m.

Dependencies

For turbocharger configurations, to create this port, set **Additional torque input** to External torque input.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
DriveshftSpd		Shaft speed	rad/s	
MechPwrLoss		Mechanical power loss	W	
ExtTrq		Applied external torque	N·m	
PwrInfo	PwrTrnsfrd	PwrCmps r	Shaft power from compressor	W
		PwrTurb	Shaft power from turbine	W
		PwrExt	Externally applied power	W
	PwrNotTrnsfrd	PwrMechLoss	Mechanical power loss	W
	PwrStored	PwrStoredDriveshft	Rate change in rotational kinetic energy	W

Cmpsr – Compressor speed

two-way connector port

Compressor speed, ω , in rad/s.

Dependencies

To create this port, for the **Configuration** parameter, select Turbocharger or Compressor only.

Turb – Turbine speed

two-way connector port

Turbine speed, ω , in N·m.

Dependencies

To create this port, for the **Configuration** parameter, select Turbocharger or Turbine only.

Parameters**Block Options****Configuration — Specify configuration**

Turbocharger (default) | Turbine only | Compressor only

Dependencies

- Selecting Turbocharger or Compressor only creates the Cmprs port.
- Selecting Turbocharger or Turbine only creates the Turb port.

Additional torque input — Specify external torque input

External torque input (default) | No external torque

Dependencies

- To enable this parameter, select a Turbocharger configuration.
- To create the Trq port, select External torque input.

Shaft inertia, J_shaft — Inertia

1.55e-5 (default) | scalar

Shaft inertia, J_{shaft} , in $\text{kg}\cdot\text{m}^2$.

Initial shaft speed, w_0 — Speed

1000 (default) | scalar

Initial drive shaft speed, ω_0 , in rad/s.

Min shaft speed, w_min — Speed

100 (default) | scalar

Minimum drive shaft speed, ω_{min} , in rad/s.

Max shaft speed, w_max — Speed

20000 (default) | scalar

Maximum drive shaft speed, ω_{max} , in rad/s.

Turbine mechanical efficiency, eta_mech — Efficiency

0.95 (default) | scalar

Mechanical efficiency of turbine η_{max} .

Dependencies

To enable this parameter, select the Turbocharger or Turbine only configuration.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

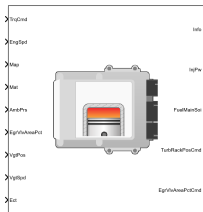
See Also

Compressor | Turbine

CI Controller

Compression-ignition controller that includes air mass flow, torque, and EGR estimation

Library: Powertrain Blockset / Propulsion / Combustion Engine Controllers



Description

The CI Controller block implements a compression-ignition (CI) controller with air mass flow, torque, exhaust gas recirculation (EGR) flow, exhaust back-pressure, and exhaust gas temperature estimation. You can use the CI Controller block in engine control design or performance, fuel economy, and emission tradeoff studies. The core engine block requires the commands that are output from the CI Controller block.

The block uses the commanded torque and measured engine speed to determine these open-loop actuator commands:

- Injector pulse-width
- Fuel injection timing
- Variable geometry turbocharger (VGT) rack position
- EGR valve area percent

The CI Controller block has two subsystems:

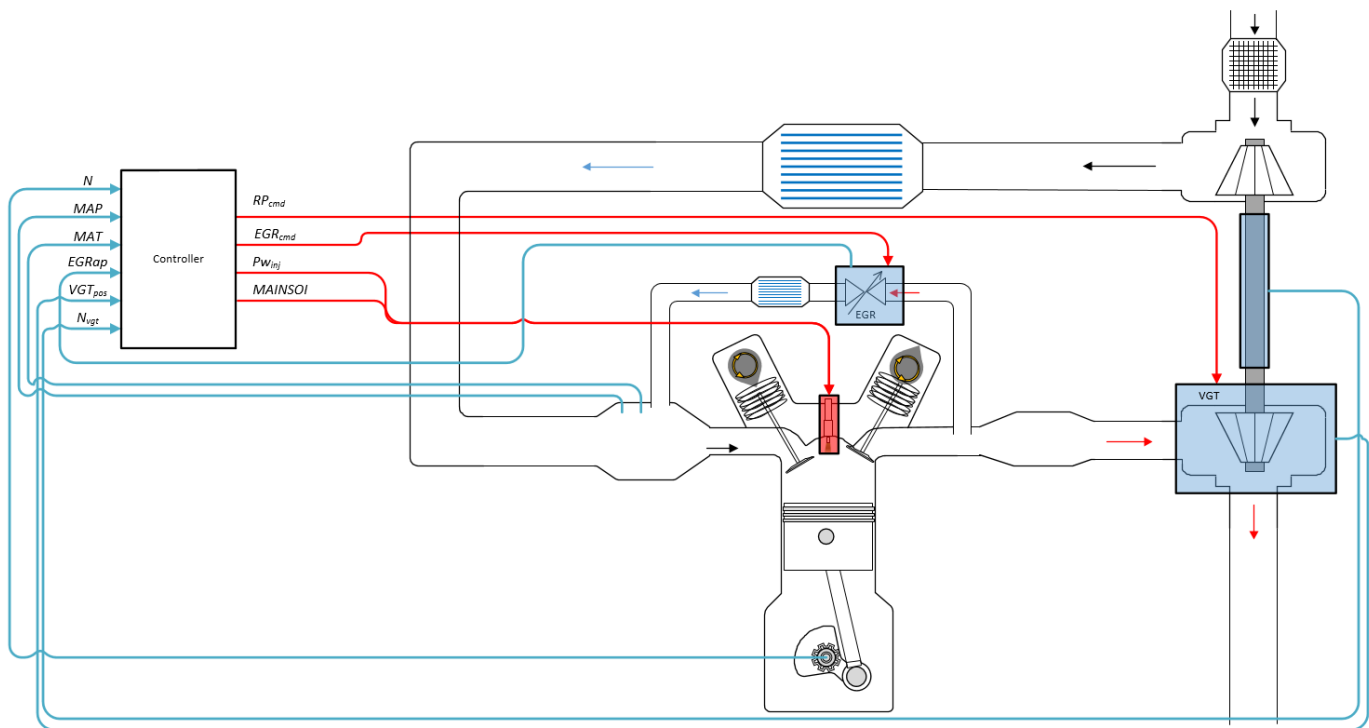
- The **Controller** subsystem — Determines the commands based on tables that are functions of commanded torque and measured engine speed.

Based On	Determines Commands for
Commanded torque	Injector pulse-width
Measured engine speed	Fuel injection timing
	VGT rack position
	EGR valve area percent

- The **Estimator** subsystem — Determines estimates based on these engine attributes.

Based On	Estimates
Measured engine speed	Air mass flow
Fuel injection timing	Torque
Cycle average intake manifold pressure and temperature	Exhaust gas temperature
Fuel injector pulse-width	Exhaust gas back-pressure
Absolute ambient pressure	EGR valve gas mass flow
EGR valve area percent	
VGT rack position	
VGT speed	

The figure illustrates the signal flow.



The figure uses these variables.

- N Engine speed
- MAP Cycle average intake manifold absolute pressure
- MAT Cycle average intake manifold gas absolute temperature
- EGR_{ap}, EGR_{cmd} EGR valve area percent and EGR valve area percent command, respectively
- VGT_{pos} VGT rack position

N_{vgt}	Corrected turbocharger speed
RP_{cmd}	VGT rack position command
PW_{inj}	Fuel injector pulse-width
$MAINSOI$	Start of injection timing for main fuel injection pulse

The Model-Based Calibration Toolbox™ was used to develop the tables that are available with the Powertrain Blockset.

Controller

The controller governs the combustion process by commanding VGT rack position, EGR valve area percent, fuel injection timing, and injector pulse-width. Feedforward lookup tables, which are functions of measured engine speed and commanded torque, determine the control commands.

Air

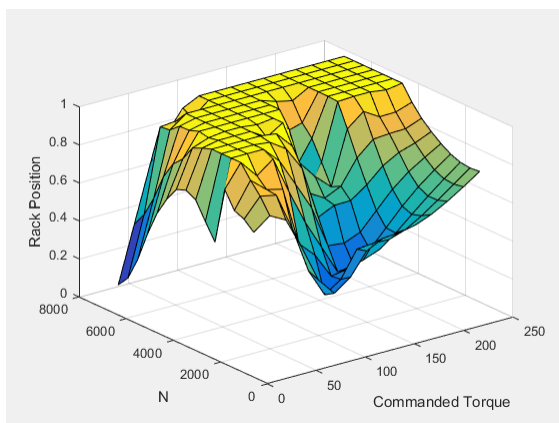
The controller commands the EGR valve area percent and VGT rack position. Changing the VGT rack position modifies the turbine flow characteristics. At low-requested torques, the rack position can reduce the exhaust back pressure, resulting in a low turbocharger speed and boost pressure. When the commanded fuel requires additional air mass flow, the rack position is set to close the turbocharger vanes, increasing the turbocharger speed and intake manifold boost pressure.

The variable geometry turbocharger (VGT) rack position lookup table is a function of commanded torque and engine speed

$$RP_{cmd} = f_{RPcmd}(Trq_{cmd}, N)$$

where:

- RP_{cmd} is VGT rack position command, in percent.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

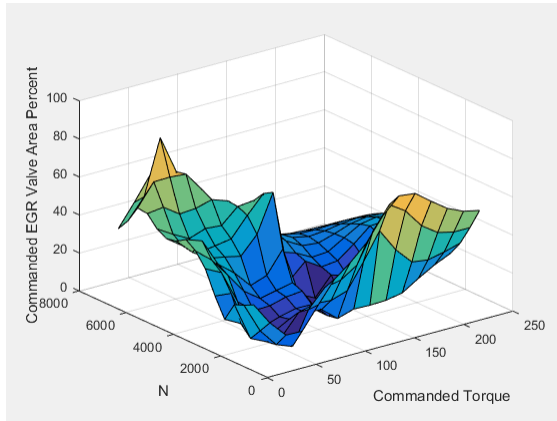


The commanded exhaust gas recirculation (EGR) valve area percent lookup table is a function of commanded torque and engine speed

$$EGR_{cmd} = f_{EGRcmd}(Trq_{cmd}, N)$$

where:

- EGR_{cmd} is commanded EGR valve area percent, in percent.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Fuel

To initiate combustion, a CI engine injects fuel directly into the combustion chamber. After the injection, the fuel spontaneously ignites, increasing cylinder pressure. The total mass of the injected fuel and main injection timing determines the torque production.

Assuming constant fuel rail pressure, the CI controller commands the injector pulse-width based on the total requested fuel mass:

$$Pw_{inj} = \frac{F_{cmd, tot}}{S_{inj}}$$

The equation uses these variables.

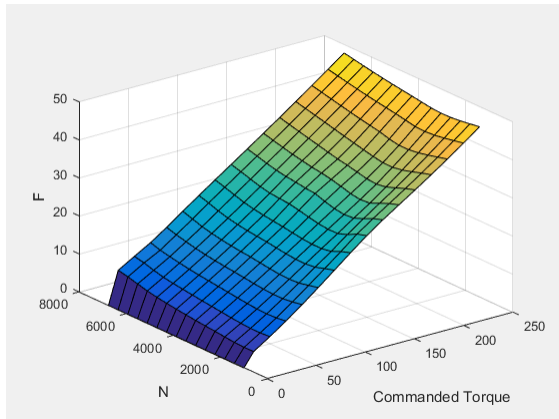
Pw_{inj}	Fuel injector pulse-width
S_{inj}	Fuel injector slope
$F_{cmd, tot}$	Commanded total fuel mass per injection
$MAINSOI$	Main start-of-injection timing
N	Engine speed

The commanded total fuel mass per injection table is a function of the torque command and engine speed

$$F_{cmd, tot} = f_{F_{cmd, tot}}(Trq_{cmd}, N)$$

where:

- $F_{cmd, tot} = F$ is commanded total fuel mass per injection, in mg per cylinder.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

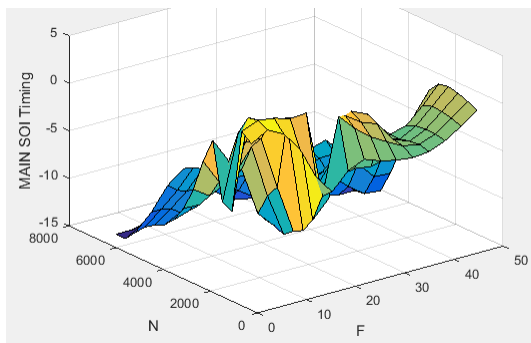


The main start-of-injection (SOI) timing lookup table is a function of commanded fuel mass and engine speed

$$MAINSOI = f(F_{cmd,tot}, N)$$

where:

- $MAINSOI$ is the main start-of-injection timing, in degrees crank angle after top dead center (degATDC).
- $F_{cmd,tot} = F$ is commanded fuel mass, in mg per injection.
- N is engine speed, in rpm.



Idle Speed

When the commanded torque is below a threshold value, the idle speed controller regulates the engine speed.

If	Idle Speed Controller
$Trq_{cmd,input} < Trq_{idlecmd,enable}$	Enabled
$Trq_{idlecmd,enable} \leq Trq_{cmd,input}$	Not enabled

The idle speed controller uses a discrete PI controller to regulate the target idle speed by commanding a torque.

The PI controller uses this transfer function:

$$C_{idle}(z) = K_{p, idle} + K_{i, idle} \frac{t_s}{z-1}$$

The idle speed commanded torque must be less than the maximum commanded torque:

$$0 \leq Trq_{idlecmd} \leq Trq_{idlecmd,max}$$

Idle speed control is active under these conditions. If the commanded input torque drops below the threshold for enabling the idle speed controller ($Trq_{cmd,input} < Trq_{idlecmd,enable}$), the commanded engine torque is given by:

$$Trq_{cmd} = \max(Trq_{cmd,input}, Trq_{idlecmd}).$$

The equations use these variables.

Trq_{cmd}	Commanded engine torque
$Trq_{cmd,input}$	Input commanded engine torque
$Trq_{idlecmd,enable}$	Threshold for enabling idle speed controller
$Trq_{idlecmd}$	Idle speed controller commanded torque
$Trq_{idlecmd,max}$	Maximum commanded torque
N_{idle}	Base idle speed
$K_{p,idle}$	Idle speed controller proportional gain
$K_{i,idle}$	Idle speed controller integral gain

Speed Limiter

To prevent over revving the engine, the block implements an engine speed limit controller that limits the engine speed to the value specified by the **Rev-limiter speed threshold** parameter on the **Controls > Idle Speed** tab.

If the engine speed, N , exceeds the engine speed limit, N_{lim} , the block sets the commanded engine torque to 0.

To smoothly transition the torque command to 0 as the engine speed approaches the speed limit, the block implements a lookup table multiplier. The lookup table multiplies the torque command by a value that ranges from 0 (engine speed exceeds limit) to 1 (engine speed does not exceed the limit).

Estimator

Using the CI Core Engine block, the CI Controller block estimates the air mass flow rate, EGR valve mass flow, exhaust back-pressure, engine torque, AFR, and exhaust temperature from sensor feedback. The **Info** port provides the estimated values, but block does not use them to determine the open-loop engine actuator commands.

Air Mass Flow

To calculate the air mass flow, the compression-ignition (CI) engine uses the “CI Engine Speed-Density Air Mass Flow Model”. The speed-density model uses the speed-density equation to calculate the engine air mass flow, relating the engine intake port mass flow to the intake manifold pressure, intake manifold temperature, and engine speed.

EGR Valve Mass Flow

To calculate the estimated exhaust gas recirculation (EGR) valve mass flow, the block calculates the EGR flow that would occur at standard temperature and pressure conditions, and then corrects the

flow to actual temperature and pressure conditions. The block EGR calculation uses estimated exhaust back-pressure, estimated exhaust temperature, standard temperature, and standard pressure.

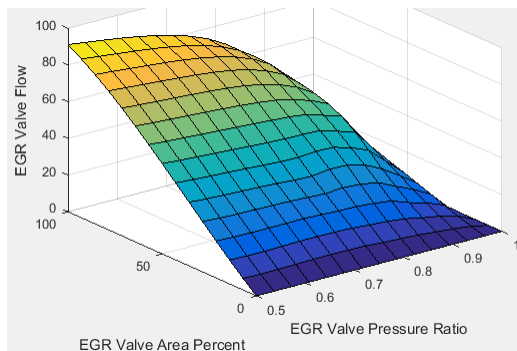
$$\dot{m}_{egr, est} = \dot{m}_{egr, std} \frac{P_{exh, est}}{P_{std}} \sqrt{\frac{T_{std}}{T_{exh, est}}}$$

- The standard exhaust gas recirculation (EGR) mass flow is a lookup table that is a function of the standard flow pressure ratio and EGR valve flow area

$$\dot{m}_{egr, std} = f\left(\frac{MAP}{P_{exh, est}}, EGRap\right)$$

where:

- $\dot{m}_{egr, std}$ is the standard EGR valve mass flow, in g/s.
- $P_{exh, est}$ is the estimated exhaust back-pressure, in Pa.
- MAP is the cycle average intake manifold absolute pressure, in Pa.
- $EGRap$ is the measured EGR valve area, in percent.



The equations use these variables.

$\dot{m}_{egr, est}$	Estimated EGR valve mass flow
$\dot{m}_{egr, std}$	Standard EGR valve mass flow
P_{std}	Standard pressure
T_{std}	Standard temperature
$T_{exh, est}$	Estimated exhaust manifold gas temperature
MAP	Measured cycle average intake manifold absolute pressure
$P_{exh, est}$	Estimated exhaust back-pressure
P_{Amb}	Absolute ambient pressure
$EGRap$	Measured EGR valve area percent

Exhaust Back-Pressure

To estimate the EGR valve mass flow, the block requires an estimate of the exhaust back-pressure. To estimate the exhaust back-pressure, the block uses the ambient pressure and the turbocharger pressure ratio.

$$P_{exh, est} = P_{Amb} Pr_{turbo}$$

For the turbocharger pressure ration calculation, the block uses two lookup tables. The first lookup table determines the approximate turbocharger pressure ratio as a function of turbocharger mass flow and corrected turbocharger speed. Using a second lookup table, the block corrects the approximate turbocharger pressure ratio for VGT rack position.

$$Pr_{turbo} = f(\dot{m}_{airstd}, N_{vgtcrr})f(VGT_{pos})$$

where:

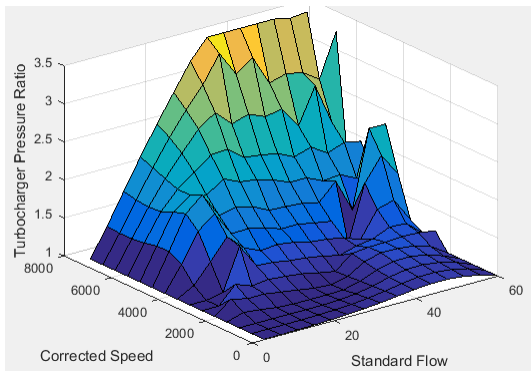
$$N_{vgtcrr} = \frac{N_{vgt}}{\sqrt{T_{exh, est}}}$$

The equations use these variables.

$\dot{m}_{egr, est}$	Estimated EGR valve mass flow
$\dot{m}_{egr, std}$	Standard EGR valve mass flow
$\dot{m}_{port, est}$	Estimated intake port mass flow rate
\dot{m}_{airstd}	Standard air mass flow
EGR_{ap}	Measured EGR valve area
MAP	Measured cycle average intake manifold absolute pressure
MAT	Measured cycle average intake manifold gas absolute temperature
P_{std}	Standard pressure
T_{std}	Standard temperature
$T_{exh, est}$	Estimated exhaust manifold gas temperature
Pr_{vgtcrr}	Turbocharger pressure ratio correction for VGT rack position
Pr_{turbo}	Turbocharger pressure ratio
$P_{exh, est}$	Estimated exhaust back-pressure
P_{Amb}	Absolute ambient pressure
N_{vgtcrr}	Corrected turbocharger speed
VGT_{pos}	Measured VGT rack position

The exhaust-back pressure calculation uses these lookup tables:

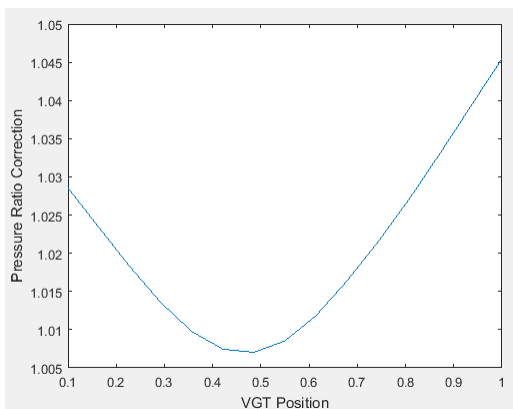
- The turbocharger pressure ratio, corrected for variable geometry turbocharger (VGT) speed, is a lookup table that is a function of the standard air mass flow and corrected turbocharger speed, $Pr_{turbo} = f(\dot{m}_{airstd}, N_{vgtcrr})$, where:
 - Pr_{turbo} is the turbocharger pressure ratio, corrected for VGT speed.
 - \dot{m}_{airstd} is the standard air mass flow, in g/s.
 - N_{vgtcrr} is the corrected turbocharger speed, in rpm/K^(1/2).



To calculate the standard air mass flow through the turbocharger, the block uses conservation of mass, the estimated intake port, and EGR mass flows (from the last estimated calculation). The calculation assumes negligible exhaust manifold filling dynamics.

$$\dot{m}_{airstd} = (\dot{m}_{port, est} - \dot{m}_{egr, est}) \frac{P_{std}}{MAP} \sqrt{\frac{MAT}{T_{std}}}$$

- The variable geometry turbocharger pressure ratio correction is a function of the rack position, $Pr_{vgtcorr} = f(VGT_{pos})$, where:
 - $Pr_{vgtcorr}$ is the turbocharger pressure ratio correction.
 - VGT_{pos} is the variable geometry turbocharger (VGT) rack position.



Engine Torque

To calculate the engine torque, you can configure the block to use either of these torque models.

Brake Torque Model	Description
“CI Engine Torque Structure Model”	<p>The CI core engine torque structure model determines the engine torque by reducing the maximum engine torque potential as these engine conditions vary from nominal:</p> <ul style="list-style-type: none"> • Start of injection (SOI) timing • Exhaust back-pressure • Burned fuel mass • Intake manifold gas pressure, temperature, and oxygen percentage • Fuel rail pressure <p>To account for the effect of post-inject fuel on torque, the model uses a calibrated torque offset table.</p>
“CI Engine Simple Torque Model”	<p>For the simple engine torque calculation, the CI engine uses a torque lookup table map that is a function of engine speed and injected fuel mass.</p>

Exhaust Temperature

The exhaust temperature calculation depends on the torque model. For both torque models, the block implements lookup tables.

Torque Model	Description	Equations
Simple Torque Lookup	Exhaust temperature lookup table is a function of the injected fuel mass and engine speed.	$T_{exh} = f_{Texh}(F, N)$
Torque Structure	<p>The nominal exhaust temperature, $T_{exh_{nom}}$, is a product of these exhaust temperature efficiencies:</p> <ul style="list-style-type: none"> • SOI timing • Intake manifold gas pressure • Intake manifold gas temperature • Intake manifold gas oxygen percentage • Fuel rail pressure • Optimal temperature <p>The exhaust temperature, $T_{exh_{nom}}$, is offset by a post temperature effect, ΔT_{post}, that accounts for post and late injections during the expansion and exhaust strokes.</p>	$T_{exh_{nom}} = SOI_{exhteff} MAP_{exhteff} MAT_{exhteff} O2p_{exhteff} FUR_{exhteff}$ $T_{exh} = T_{exh_{nom}} + \Delta T_{post}$ $SOI_{exhteff} = f_{SOI_{exhteff}}(\Delta SOI, N)$ $MAP_{exhteff} = f_{MAP_{exhteff}}(MAP_{ratio}, \lambda)$ $MAT_{exhteff} = f_{MAT_{exhteff}}(\Delta MAT, N)$ $O2p_{exhteff} = f_{O2p_{exhteff}}(\Delta O2p, N)$ $Texh_{opt} = f_{Texh}(F, N)$

The equations use these variables.

F	Compression stroke injected fuel mass
N	Engine speed
T_{exh}	Exhaust manifold gas temperature
$T_{exh_{opt}}$	Optimal exhaust manifold gas temperature
ΔT_{post}	Post injection temperature effect
$T_{exh_{nom}}$	Nominal exhaust temperature
SOI_{exheff}	Main SOI exhaust temperature efficiency multiplier
ΔSOI	Main SOI timing relative to optimal timing
MAP_{exheff}	Intake manifold gas pressure exhaust temperature efficiency multiplier
MAP_{ratio}	Intake manifold gas pressure ratio relative to optimal pressure ratio
λ	Intake manifold gas lambda
MAT_{exheff}	Intake manifold gas temperature exhaust temperature efficiency multiplier
ΔMAT	Intake manifold gas temperature relative to optimal temperature
$O2P_{exheff}$	Intake manifold gas oxygen exhaust temperature efficiency multiplier
$\Delta O2P$	Intake gas oxygen percent relative to optimal
$FUELP_{exheff}$	Fuel rail pressure exhaust temperature efficiency multiplier
$\Delta FUELP$	Fuel rail pressure relative to optimal

Air-Fuel Ratio

The measured engine speed and fuel injector pulse-width determine the commanded fuel mass flow rate:

$$\dot{m}_{fuel,cmd} = \frac{NS_{inj}Pw_{inj}N_{cyl}}{Cps\left(\frac{60s}{min}\right)\left(\frac{1000mg}{g}\right)}$$

The commanded total fuel mass flow and estimated port mass flow rates determine the estimated AFR:

$$AFR_{est} = \frac{\dot{m}_{port,est}}{\dot{m}_{fuel,cmd}}$$

The equations use these variables.

Pw_{inj}	Fuel injector pulse-width
AFR_{est}	Estimated air-fuel ratio
$\dot{m}_{fuel,cmd}$	Commanded fuel mass flow rate
S_{inj}	Fuel injector slope
N	Engine speed
N_{cyl}	Number of engine cylinders
Cps	Crankshaft revolutions per power stroke, rev/stroke
$\dot{m}_{port,est}$	Total estimated engine air mass flow at intake ports

Ports

Input

TrqCmd — Commanded engine torque

scalar

Commanded engine torque, $Trq_{cmd,input}$, in N·m.**EngSpd — Measured engine speed**

scalar

Measured engine speed, N , in rpm.**Map — Measured intake manifold absolute pressure**

scalar

Measured intake manifold absolute pressure, MAP , in Pa.**Mat — Measured intake manifold absolute temperature**

scalar

Measured intake manifold absolute temperature, MAT , in K.**AmbPrs — Ambient pressure**

scalar

Absolute ambient pressure, P_{Amb} , in Pa.**EgrVlvAreaPct — EGR valve area percent**

scalar

Measured EGR valve area percent, EGR_{ap} , in %.**VgtPos — VGT speed**

scalar

Measured VGT rack position, VGT_{pos} .**VgtSpd — VGT speed**

scalar

Measured VGT speed, N_{vgt} , in rpm.**Ect — Engine cooling temperature**

scalar

Engine cooling temperature, $T_{coolant}$, in K.**IgSw — Ignition switch**

Boolean

State of the vehicle ignition switch, dimensionless.

Dependencies

To create this port, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

ESSEnable – Engine Stop-Start Enable

Boolean

Command to enable or disable the stop-start logic, dimensionless.

Dependencies

To create this port, on the **Stop-Start** tab, select **Enable Engine Stop-Start**. Select **External Enable Port**.

Output**Info – Bus signal**

bus

Bus signal containing these block calculations.

Signal	Description	Variable	Units
InjPw	Fuel injector pulse-width	Pw_{inj}	ms
EgrVlvAreaPctCmd	EGR valve area percent command	EGR_{cmd}	%
TurbRackPosCmd	VGT rack position command	RP_{cmd}	N/A
TrqCmd	Engine torque	Trq_{cmd}	N·m
FuelMassTotCmd	Commanded total fuel mass per injection	$F_{cmd,tot}$	mg
FuelMainSoi	Main start-of-injection timing	$MAINSOI$	degATDC
FuelMassFlwCmd	Commanded fuel mass flow rate	$\dot{m}_{fuel,cmd}$	kg/s
EstIntkPortMassFlw	Estimated port mass flow rate	$\dot{m}_{port,est}$	kg/s
EstEngTrq	Estimated engine torque	Trq_{est}	N·m
EstExhManGasTemp	Estimated exhaust manifold gas temperature	$T_{exh,est}$	K
EstExhPrs	Estimated exhaust back-pressure	P_{ex}	Pa
EstEGRFlow	EstEGRFlow	EstEGRFlow	EstEGRFlow
EstAfr	Estimated air-fuel ratio	AFR_{est}	N/A
EngRevLimAct	Flag that indicates if rev-limiter control is active	N/A	N/A

InjPw – Fuel injector pulse-width

scalar

Fuel injector pulse-width, Pw_{inj} , in ms.

FuelMainSoi – Fuel main injecting timing

scalar

Main start-of-injection timing, $MAINSOI$, in degrees crank angle after top dead center (degATDC).

TurbRackPosCmd — Rack position

scalar

VGT rack position command, RP_{cmd} .

EgrVlvAreaPctCmd — Intake cam phaser angle command

scalar

EGR valve area percent command, EGR_{cmd} .

Parameters

Controls

Air - EGR

EGR valve area percent, f_egr cmd — Lookup table

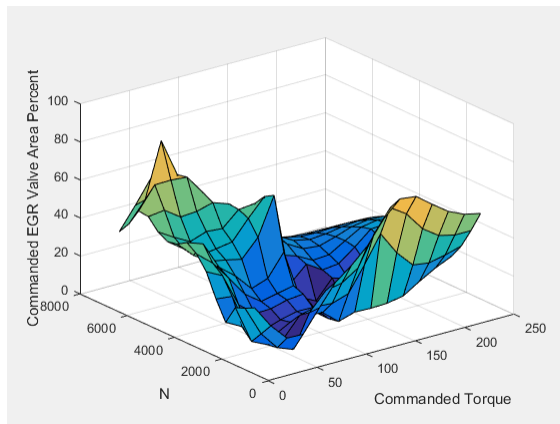
array

The commanded exhaust gas recirculation (EGR) valve area percent lookup table is a function of commanded torque and engine speed

$$EGR_{cmd} = f_{EGRcmd}(Trq_{cmd}, N)$$

where:

- EGR_{cmd} is commanded EGR valve area percent, in percent.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Commanded torque breakpoints, f_egr_tq_bpt — Breakpoints

[10 26.43 42.86 59.29 75.71 92.14 108.6 125 141.4 157.9 174.3 190.7 207.1 223.6 240] (default) | vector

Commanded torque breakpoints, in N·m.

Speed breakpoints, f_egr_n_bpt — Breakpoints

[1000 1411 1821 2232 2643 3054 3464 3875 4286 4696 5107 5518 5929 6339 6750] (default) | vector

Speed breakpoints, in rpm.

Air - VGR

VGT rack position table, $f_{rp_{cmd}}$ – Lookup table

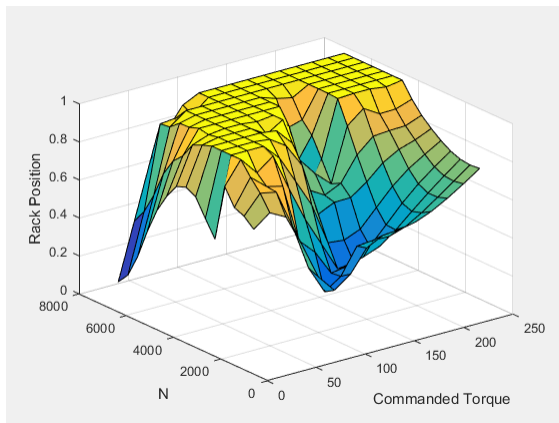
array

The variable geometry turbocharger (VGT) rack position lookup table is a function of commanded torque and engine speed

$$RP_{cmd} = f_{RP_{cmd}}(Trq_{cmd}, N)$$

where:

- RP_{cmd} is VGT rack position command, in percent.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Commanded torque breakpoints, $f_{rp_{tq}_{bpt}}$ – Breakpoints

[10 26.43 42.86 59.29 75.71 92.14 108.6 125 141.4 157.9 174.3 190.7 207.1 223.6 240] (default) | vector

Breakpoints, in N·m.

Speed breakpoints, $f_{rp_{n}_{bpt}}$ – Breakpoints

[1000 1411 1821 2232 2643 3054 3464 3875 4286 4696 5107 5518 5929 6339 6750] (default) | vector

Breakpoints, in rpm.

Fuel

Injector slope, S_{inj} – Slope

6.452 (default) | scalar

Fuel injector slope, S_{inj} , in mg/ms.

Stoichiometric air-fuel ratio, afr_{stoich} – Ratio

14.6 (default) | scalar

Stoichiometric air-fuel ratio, AFR_{stoich} .

Fuel lower heating value, fuel_lhv – Heat

42e6 (default) | scalar

Fuel lower heating value, in J/kg.

Fuel mass per injection table, f_fcnd_tot – Lookup table

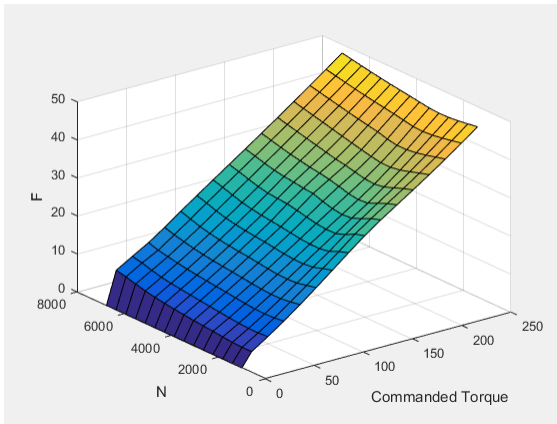
array

The commanded total fuel mass per injection table is a function of the torque command and engine speed

$$F_{cmd,tot} = f_{F_{cmd,tot}}(Trq_{cmd}, N)$$

where:

- $F_{cmd,tot} = F$ is commanded total fuel mass per injection, in mg per cylinder.
- Trq_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Fuel main injection timing table, f_main_soi – Lookup table

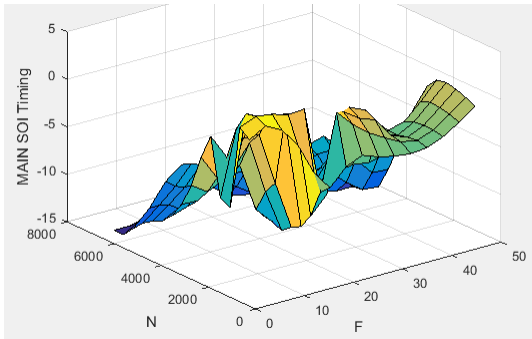
array

The main start-of-injection (SOI) timing lookup table is a function of commanded fuel mass and engine speed

$$MAINSOI = f(F_{cmd,tot}, N)$$

where:

- $MAINSOI$ is the main start-of-injection timing, in degrees crank angle after top dead center (degATDC).
- $F_{cmd,tot} = F$ is commanded fuel mass, in mg per injection.
- N is engine speed, in rpm.



Fuel main injection timing fuel breakpoints, $f_main_soi_f_bpt$ – Breakpoints
vector

Fuel main injection timing fuel breakpoints, in mg per injection.

Fuel main injection timing speed breakpoints, $f_main_soi_n_bpt$ – Breakpoints
[1000, 1410.71428571429, 1821.42857142857, 2232.14285714286, 2642.85714285714, 3053.57142857143, 3464.28571428571, 3875, 4285.71428571429, 4696.42857142857, 5107.14285714286, 5517.85714285714, 5928.57142857143, 6339.28571428572, 6750] (default) |
vector

Fuel main injection timing speed breakpoints, in rpm.

Commanded torque breakpoints, $f_f_tot_tq_bpt$ – Breakpoints
[0 10 26.43 42.86 59.29 75.71 92.14 108.6 125 141.4 157.9 174.3 190.7 207.1 223.6 240] (default) | vector

Commanded torque breakpoints, in N·m.

Speed breakpoints, $f_f_tot_n_bpt$ – Breakpoints
[1000 1411 1821 2232 2643 3054 3464 3875 4286 4696 5107 5518 5929 6339 6750] (default) | vector

Speed breakpoints, in rpm.

Idle Speed

Base idle speed, N_idle – Speed
750 (default) | scalar

Base idle speed, N_{idle} , in rpm.

Enable torque command limit, $Trq_idlecmd_enable$ – Torque
1 (default) | scalar

Torque to enable the idle speed controller, $Trq_{idlecmd,enable}$, in N·m.

Maximum torque command, $Trq_idlecmd_max$ – Torque
50 (default) | scalar

Maximum idle controller commanded torque, $Trq_{idlecmd,max}$, in N·m.

Proportional gain, Kp_idle – PI Controller
0.05 (default) | scalar

Proportional gain for idle speed control, $K_{p, idle}$, in N·m/rpm.

Integral gain, K_i_{idle} – PI Controller

0.2 (default) | scalar

Integral gain for idle speed control, $K_{i, idle}$, in N·m/(rpm·s).

Rev-limiter speed threshold – Engine speed limit

scalar

Engine speed limit, N_{lim} , in rpm.

If the engine speed, N , exceeds the engine speed limit, N_{lim} , the block sets the commanded engine torque to 0.

To smoothly transition the torque command to 0 as the engine speed approaches the speed limit, the block implements a lookup table multiplier. The lookup table multiplies the torque command by a value that ranges from 0 (engine speed exceeds limit) to 1 (engine speed does not exceed the limit).

Stop-Start**Enable Engine Stop-Start – Select to enable the engine stop-start logic**

off (default) | on

Select to enable the engine stop-start logic. Selecting this option will activate additional parameters to modify the behavior of the Engine Stop-Start block.

External Enable Port – Create input port

off (default) | on

Select to add a port to the engine controller block which enables or disables the stop-start logic.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Engine stop time, EngStopTime [s] – Engine stop time

5 (default) | scalar

Engine stop time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Catalyst light off time, CatLightOffTime [s] – Catalyst light off time

0 (default) | scalar

Catalyst light off time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Sample time, Ts [s] – Sample time

0.01 (default) | scalar

Sample time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Estimation**Air****Number of cylinders, NCyl — Engine cylinders**

4 (default) | scalar

Number of engine cylinders, N_{cyl} .

Crank revolutions per power stroke, Cps — Revolutions per stroke

2 (default) | scalar

Crankshaft revolutions per power stroke, Cps , in rev/stroke.

Total displaced volume, Vd — Volume

0.0015 (default) | scalar

Displaced volume, V_d , in m^3 .

Ideal gas constant air, Rair — Constant

287 (default) | scalar

Ideal gas constant, R_{air} , in $J/(kg \cdot K)$.

Air standard pressure, Pstd — Pressure

101325 (default) | scalar

Standard air pressure, P_{std} , in Pa.

Air standard temperature, Tstd — Temperature

293.15 (default) | scalar

Standard air temperature, T_{std} , in K.

Speed density volumetric efficiency, f_nv — Lookup table

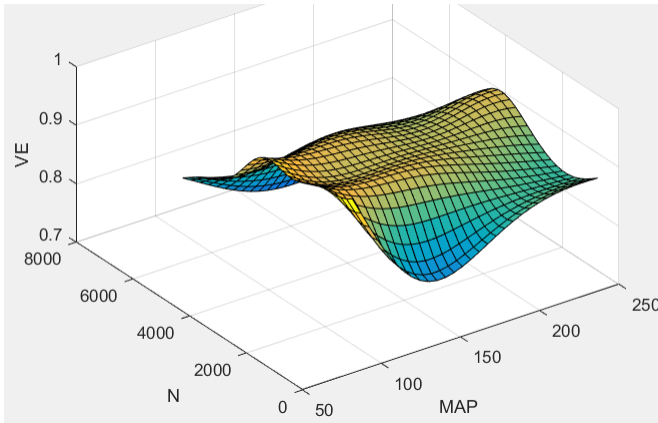
array

The volumetric efficiency lookup table is a function of the intake manifold absolute pressure at intake valve closing (IVC) and engine speed

$$\eta_v = f_{\eta_v}(MAP, N)$$

where:

- η_v is engine volumetric efficiency, dimensionless.
- MAP is intake manifold absolute pressure, in KPa.
- N is engine speed, in rpm.



Speed density intake manifold pressure breakpoints, `f_nv_prs_bpt` — Breakpoints

[95 100.3 105.7 111 116.4 121.7 127.1 132.4 137.8 143.1 148.4 153.8 159.1
164.5 169.8 175.2 180.5 185.9 191.2 196.6 201.9 207.2 212.6 217.9 223.3 228.6
234 239.3 244.7 250] (default) | vector

Intake manifold pressure breakpoints for speed-density volumetric efficiency lookup table, in KPa.

Speed density engine speed breakpoints, `f_nv_n_bpt` — Breakpoints

[750 956.9 1164 1371 1578 1784 1991 2198 2405 2612 2819 3026 3233 3440 3647
3853 4060 4267 4474 4681 4888 5095 5302 5509 5716 5922 6129 6336 6543 6750]
(default) | vector

Engine speed breakpoints for speed-density volumetric efficiency lookup table, in rpm.

EGR valve standard flow calibration, `f_egr_stdflow` — Lookup table

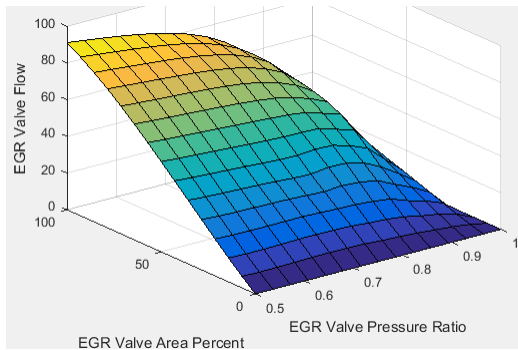
array

The standard exhaust gas recirculation (EGR) mass flow is a lookup table that is a function of the standard flow pressure ratio and EGR valve flow area

$$\dot{m}_{egr, std} = f\left(\frac{MAP}{P_{exh, est}}, EGRap\right)$$

where:

- $\dot{m}_{egr, std}$ is the standard EGR valve mass flow, in g/s.
- $P_{exh, est}$ is the estimated exhaust back-pressure, in Pa.
- MAP is the cycle average intake manifold absolute pressure, in Pa.
- $EGRap$ is the measured EGR valve area, in percent.



EGR valve standard flow pressure ratio breakpoints, $f_egr_stdflow_pr_bpt$ – Breakpoints
vector

EGR valve standard flow pressure ratio breakpoints, dimensionless.

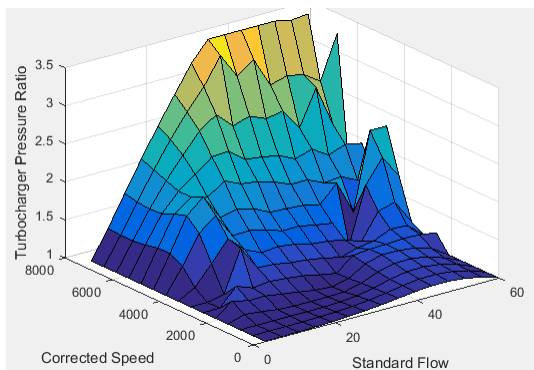
EGR valve standard flow area percent breakpoints, $f_egr_stdflow_egrap_bpt$ – Breakpoints
vector

EGR valve standard flow area percent breakpoints, in percent.

Turbocharger pressure ratio, f_turbo_pr – Lookup table
array

The turbocharger pressure ratio, corrected for variable geometry turbocharger (VGT) speed, is a lookup table that is a function of the standard air mass flow and corrected turbocharger speed, $Pr_{turbo} = f(\dot{m}_{airstd}, N_{vgtcorr})$, where:

- Pr_{turbo} is the turbocharger pressure ratio, corrected for VGT speed.
- \dot{m}_{airstd} is the standard air mass flow, in g/s.
- $N_{vgtcorr}$ is the corrected turbocharger speed, in rpm/K^(1/2).



Turbocharger pressure ratio standard flow breakpoints, $f_turbo_pr_stdflow_bpt$ – Breakpoints
vector

Turbocharger pressure ratio standard flow breakpoints, in g/s.

Turbocharger pressure ratio corrected speed breakpoints, $f_turbo_pr_corrspd_bpt$ – Breakpoints

vector

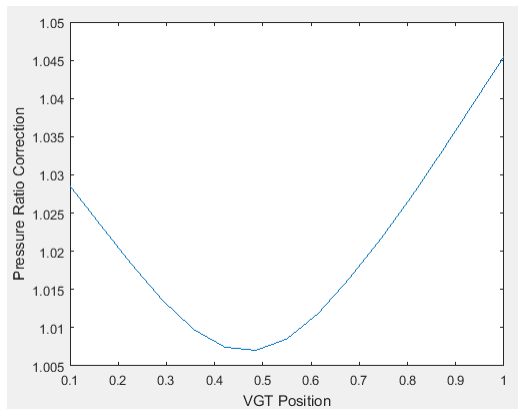
Turbocharger pressure ratio corrected speed breakpoints, in $\text{rpm}/\text{K}^{(1/2)}$.

Turbocharger pressure ratio VGT position correction, $f_turbo_pr_vgtposcorr$ – Lookup table

array

The variable geometry turbocharger pressure ratio correction is a function of the rack position, $Pr_{vgtpos} = f(VGT_{pos})$, where:

- Pr_{vgtpos} is the turbocharger pressure ratio correction.
- VGT_{pos} is the variable geometry turbocharger (VGT) rack position.



Turbocharger pressure ratio VGT position correction breakpoints, $f_turbo_pr_vgtposcorr_bpt$ – Breakpoints

vector

Turbocharger pressure ratio VGT position correction breakpoints, dimensionless.

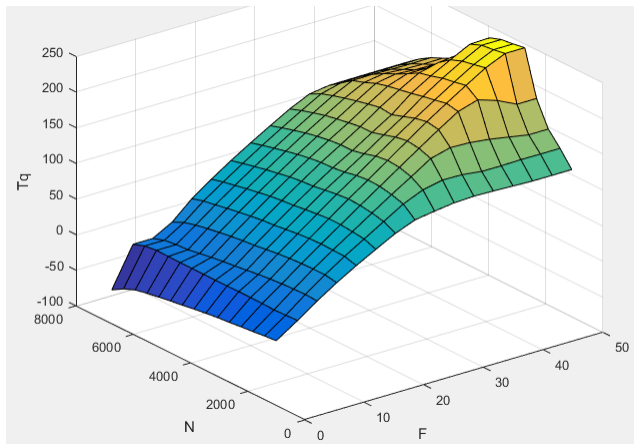
Torque - Simple Torque Lookup

Torque table, f_tq_nf – Lookup table

array

For the simple torque lookup table model, the CI engine uses a lookup table is a function of engine speed and injected fuel mass, $T_{brake} = f_{Tnf}(F, N)$, where:

- $Tq = T_{brake}$ is engine brake torque after accounting for engine mechanical and pumping friction effects, in $\text{N}\cdot\text{m}$.
- F is injected fuel mass, in mg per injection.
- N is engine speed, in rpm .



Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque table fuel mass per injection breakpoints, f_tq_nf_f_bpt – Breakpoints
 [0 3.5714 7.1429 10.7143 14.2857 17.8571 21.4286 25 28.5714 32.1429 35.7143
 39.2857 42.8571 46.4286 50] (default) | vector

Torque table fuel mass per injection breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque table speed breakpoints, f_tq_nf_n_bpt – Breakpoints
 [1000 1410.7143 1821.4286 2232.1429 2642.8571 3053.5714 3464.2857 3875
 4285.7143 4696.4286 5107.1429 5517.8571 5928.5714 6339.2857 6750] (default) |
 vector

Engine speed breakpoints, in rpm.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque - Torque Structure

Fuel mass per injection breakpoints, f_tqs_f_bpt – Breakpoints
 vector

Fuel mass per injection breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Engine speed breakpoints, f_tqs_n_bpt – Breakpoints
 [500 750 1000 1250 1500 1750 2000 2250 2500 2750 3000 3250 3500 3750 4000]
 (default) | vector

Engine speed breakpoints, in rpm.

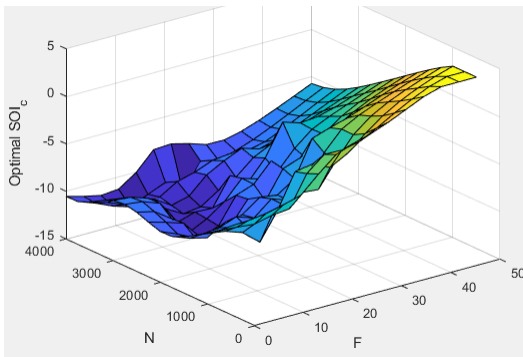
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal main start of injection timing, f_tqs_mainsoi – Optimal MAINSOI array

The optimal main start of injection (SOI) timing lookup table, f_{SOI_c} , is a function of the engine speed and injected fuel mass, $SOI_c = f_{SOI_c}(F, N)$, where:

- SOI_c is optimal SOI timing, in degATDC.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



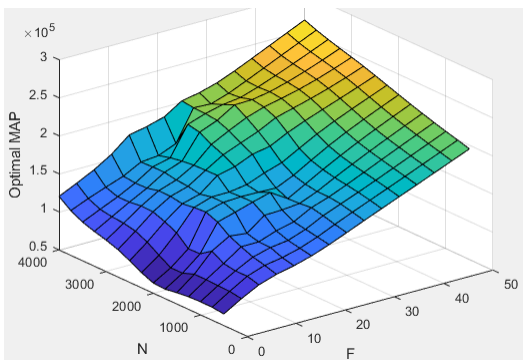
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake manifold gas pressure, f_tqs_map – Optimal intake MAP array

The optimal intake manifold gas pressure lookup table, f_{MAP} , is a function of the engine speed and injected fuel mass, $MAP = f_{MAP}(F, N)$, where:

- MAP is optimal intake manifold gas pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



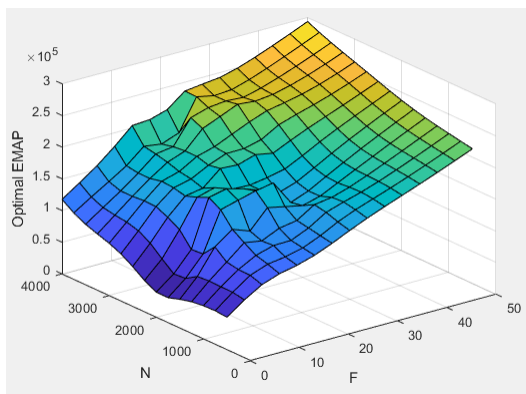
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal exhaust manifold gas pressure, f_{tqs_emap} – Optimal exhaust MAP array

The optimal exhaust manifold gas pressure lookup table, f_{EMAP} , is a function of the engine speed and injected fuel mass, $EMAP = f_{EMAP}(F, N)$, where:

- $EMAP$ is optimal exhaust manifold gas pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



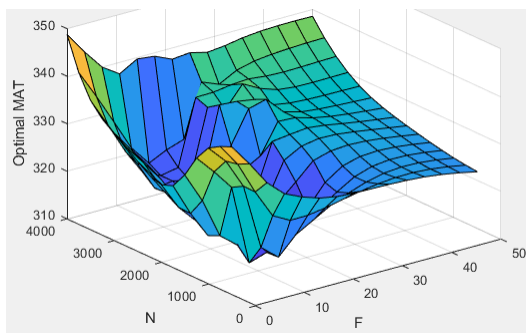
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake manifold gas temperature, f_{tqs_mat} – Optimal intake MAT array

The optimal intake manifold gas temperature lookup table, f_{MAT} , is a function of the engine speed and injected fuel mass, $MAT = f_{MAT}(F, N)$, where:

- MAT is optimal intake manifold gas temperature, in K.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



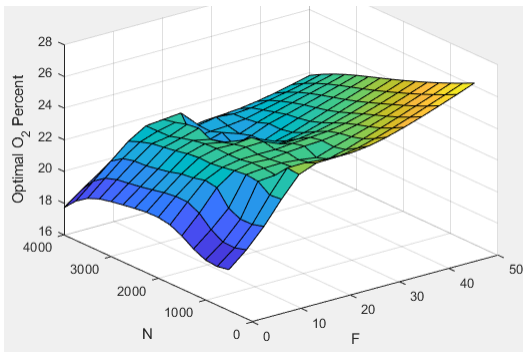
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake gas oxygen percent, f_tqs_o2pct – Optimal intake gas oxygen array

The optimal intake gas oxygen percent lookup table, f_{O_2} , is a function of the engine speed and injected fuel mass, $O2PCT = f_{O_2}(F,N)$, where:

- $O2PCT$ is optimal intake gas oxygen, in percent.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



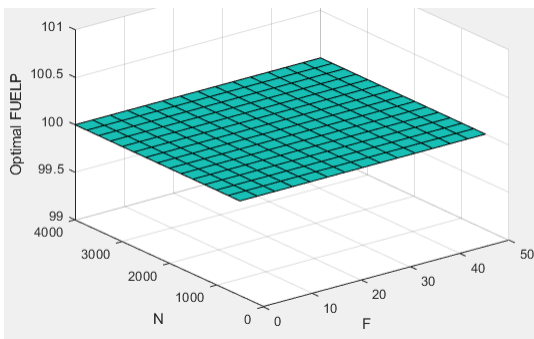
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal fuel rail pressure, f_tqs_fuelpress – Optimal fuel rail pressure array

The optimal fuel rail pressure lookup table, f_{fuelp} , is a function of the engine speed and injected fuel mass, $FUELP = f_{fuelp}(F,N)$, where:

- $FUELP$ is optimal fuel rail pressure, in MPa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

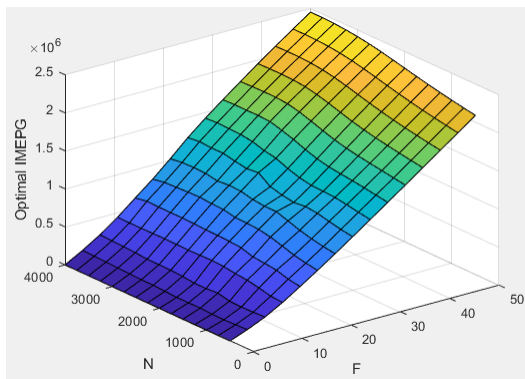
To enable this parameter, for **Torque model**, select Torque Structure.

Optimal gross indicated mean effective pressure, `f_tqs_imepg` – Optimal mean effective pressure

array

The optimal gross indicated mean effective pressure lookup table, f_{imepg} , is a function of the engine speed and injected fuel mass, $IMEPG = f_{imepg}(F, N)$, where:

- $IMEPG$ is optimal gross indicated mean effective pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

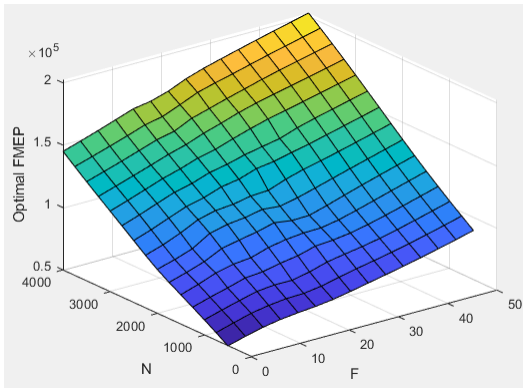
To enable this parameter, for **Torque model**, select Torque Structure.

Optimal friction mean effective pressure, `f_tqs_fmep` – Optimal friction mean effective pressure

array

The optimal friction mean effective pressure lookup table, f_{fmep} , is a function of the engine speed and injected fuel mass, $FMEP = f_{fmep}(F, N)$, where:

- $FMEP$ is optimal friction mean effective pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



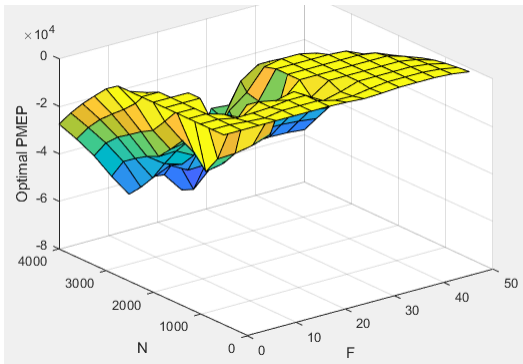
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal pumping mean effective pressure, f_tqs_pmp – Optimal pumping mean effective pressure
array

The optimal pumping mean effective pressure lookup table, f_{pmp} , is a function of the engine speed and injected fuel mass, $PMEP = f_{pmp}(F, N)$, where:

- $PMEP$ is optimal pumping mean effective pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Friction multiplier as a function of temperature, f_tqs_fric_temp_mod – Friction multiplier
array

Friction multiplier as a function of temperature, dimensionless.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Friction multiplier temperature breakpoints, $f_tqs_fric_temp_bpt$ – Breakpoints vector

Friction multiplier temperature breakpoints, in K.

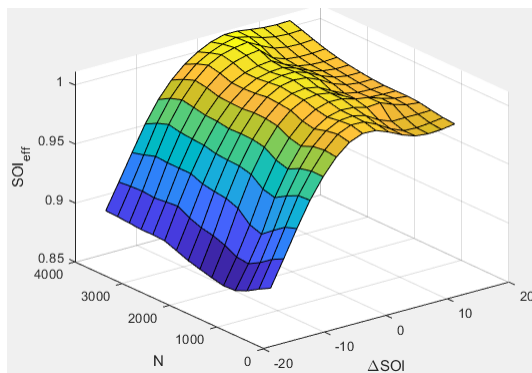
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing efficiency multiplier, $f_tqs_mainsoi_eff$ – MAINSOI efficiency multiplier array

The main start of injection (SOI) timing efficiency multiplier lookup table, $f_{SOI_{eff}}$, is a function of the engine speed and main SOI timing relative to optimal timing, $SOI_{eff} = f_{SOI_{eff}}(\Delta SOI, N)$, where:

- SOI_{eff} is main SOI timing efficiency multiplier, dimensionless.
- ΔSOI is main SOI timing relative to optimal timing, in degBTDC.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing relative to optimal timing breakpoints, $f_tqs_mainsoi_delta_bpt$ – Breakpoints vector

Main start of injection timing relative to optimal timing breakpoints, in degBTDC.

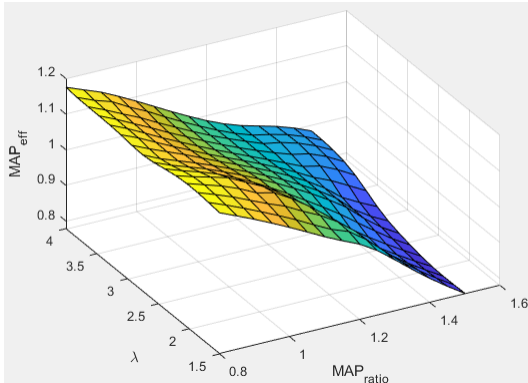
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure efficiency multiplier, $f_tqs_map_eff$ – Intake pressure efficiency multiplier array

The intake manifold gas pressure efficiency multiplier lookup table, $f_{MAP_{eff}}$, is a function of the intake manifold gas pressure ratio relative to optimal pressure ratio and lambda, $MAP_{eff} = f_{MAP_{eff}}(MAP_{ratio}, \lambda)$, where:

- MAP_{eff} is intake manifold gas pressure efficiency multiplier, dimensionless.
- MAP_{ratio} is intake manifold gas pressure ratio relative to optimal pressure ratio, dimensionless.
- λ is intake manifold gas lambda, dimensionless.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure ratio relative to optimal pressure ratio breakpoints, f_tqs_map_ratio_bpt — Breakpoints

[0.8;0.85;0.9;0.95;1;1.05;1.1;1.15;1.2;1.25;1.3;1.35;1.4;1.45;1.5] (default) | vector

Intake manifold gas pressure ratio relative to optimal pressure ratio breakpoints, dimensionless.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas lambda breakpoints, f_tqs_lambda_bpt — Breakpoints

[1.5 1.678571428571429 1.857142857142857 2.035714285714286 2.214285714285714 2.392857142857143 2.571428571428571 2.75 2.928571428571429 3.107142857142857 3.285714285714286 3.464285714285714 3.642857142857143 3.821428571428572 4] (default) | vector

Intake manifold gas lambda breakpoints, dimensionless.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

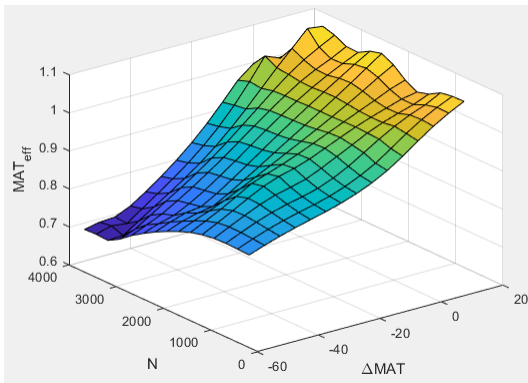
Intake manifold gas temperature efficiency multiplier, f_tqs_mat_eff — Intake temperature efficiency multiplier

array

The intake manifold gas temperature efficiency multiplier lookup table, $f_{MAT_{eff}}$, is a function of the engine speed and intake manifold gas temperature relative to optimal temperature, $MAT_{eff} = f_{MAT_{eff}}(\Delta MAT, N)$, where:

- MAT_{eff} is intake manifold gas temperature efficiency multiplier, dimensionless.
- ΔMAT is intake manifold gas temperature relative to optimal temperature, in K.

- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas temperature relative to optimal gas temperature breakpoints, $f_{tqs_mat_delta_bpt}$ – Breakpoints

`[-55; -50; -45; -40; -35; -30; -25; -20; -15; -10; -5; 0; 5; 10; 15]` (default) | vector

Intake manifold gas temperature relative to optimal gas temperature breakpoints, in K.

Dependencies

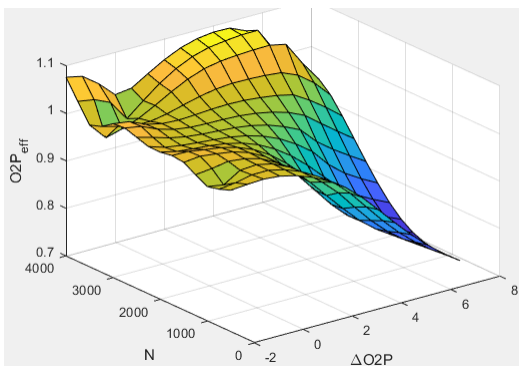
To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas oxygen efficiency multiplier, $f_{tqs_o2pct_eff}$ – Intake oxygen efficiency multiplier

array

The intake manifold gas oxygen efficiency multiplier lookup table, $f_{O2P_{eff}}$, is a function of the engine speed and intake manifold gas oxygen percent relative to optimal, $O2P_{eff} = f_{O2P_{eff}}(\Delta O2P, N)$, where:

- $O2P_{eff}$ is intake manifold gas oxygen efficiency multiplier, dimensionless.
- $\Delta O2P$ is intake gas oxygen percent relative to optimal, in percent.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake gas oxygen percent relative to optimal breakpoints, f_tqs_o2pct_delta_bpt – Breakpoints
vector

Intake gas oxygen percent relative to optimal breakpoints, in percent.

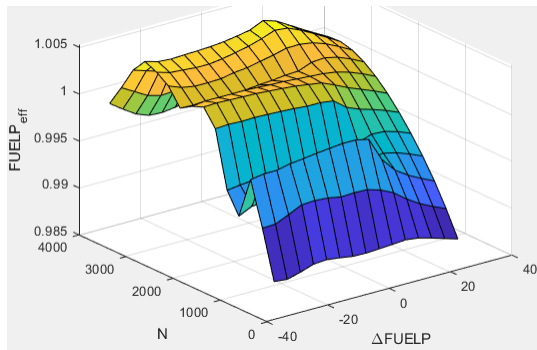
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure efficiency multiplier, f_tqs_fuelpress_eff – Efficiency multiplier
array

The fuel rail pressure efficiency multiplier lookup table, $f_{FUELP_{eff}}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $FUELP_{eff} = f_{FUELP_{eff}}(\Delta FUELP, N)$, where:

- $FUELP_{eff}$ is fuel rail pressure efficiency multiplier, dimensionless.
- $\Delta FUELP$ is fuel rail pressure relative to optimal, in MPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure relative to optimal breakpoints, f_tqs_fuelpress_delta_bpt – Breakpoints
vector

Fuel rail pressure relative to optimal breakpoints, in MPa.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel mass injection type identifier, f_tqs_f_inj_type – Type identifier
0 (default) | scalar

Fuel mass injection type identifier, dimensionless.

In the CI Core Engine and CI Controller blocks, you can represent multiple injections with the start of injection (SOI) and fuel mass inputs to the model. To specify the type of injection, use the **Fuel mass injection type identifier** parameter.

Type of Injection	Parameter Value
Pilot	0
Main	1
Post	2
Passed	3

The model considers Passed fuel injections and fuel injected later than a threshold to be unburned fuel. Use the **Maximum start of injection angle for burned fuel, f_tqs_f_burned_soi_limit** parameter to specify the threshold.

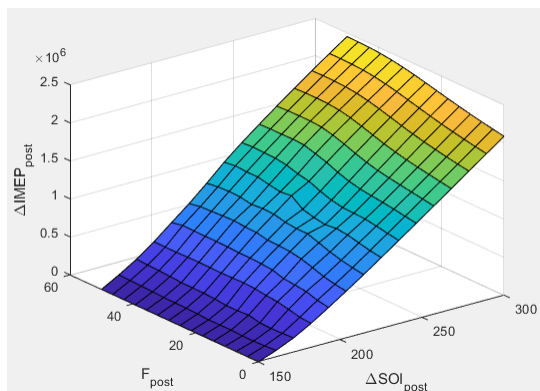
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject correction, f_tqs_imep_post_corr – Post inject correction
array

The indicated mean effective pressure post inject correction lookup table, $f_{IMEP_{post}}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $\Delta IMEP_{post} = f_{IMEP_{post}}(\Delta SOI_{post}, F_{post})$, where:

- $\Delta IMEP_{post}$ is indicated mean effective pressure post inject correction, in Pa.
- ΔSOI_{post} is indicated mean effective pressure post inject start of inject timing centroid, in degATDC.
- F_{post} is indicated mean effective pressure post inject mass sum, in mg per injection.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject mass sum breakpoints, f_tqs_f_post_sum_bpt – Breakpoints

[0 3.571428571428572 7.142857142857143 10.71428571428571 14.28571428571429 17.85714285714286 21.42857142857143 25 28.57142857142857 32.14285714285715

35.71428571428572 39.28571428571428 42.85714285714285 46.42857142857143 50]
(default) | vector

Indicated mean effective pressure post inject mass sum breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject start of inject timing centroid breakpoints, f_tqs_soi_post_cent_bpt — Breakpoints

[150 160.7142857142857 171.4285714285714 182.1428571428571 192.8571428571429
203.5714285714286 214.2857142857143 225 235.7142857142857 246.4285714285714
257.1428571428571 267.8571428571429 278.5714285714286 289.2857142857143 300]
(default) | vector

Indicated mean effective pressure post inject start of inject timing centroid breakpoints, in degATDC.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Maximum start of injection angle for burned fuel, f_tqs_f_burned_soi_limit — Maximum SOI angle for burned fuel

500 (default) | scalar

Maximum start of injection angle for burned fuel, in degATDC.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Exhaust

Exhaust gas specific heat at constant pressure, cp_exh — Specific heat

1005 (default) | scalar

Exhaust gas-specific heat, $C_{p_{exh}}$, in J/(kg·K).

Exhaust Temperature - Simple Torque Lookup

Exhaust temperature table, f_t_exh — Lookup table

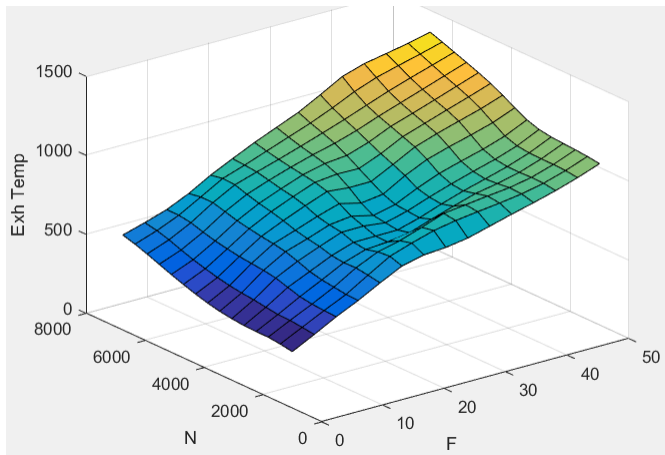
array

The lookup table for the exhaust temperature is a function of injected fuel mass and engine speed

$$T_{exh} = f_{T_{exh}}(F, N)$$

where:

- T_{exh} is exhaust temperature, in K.
- F is injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Fuel mass per injection breakpoints, $f_{t_exh_f_bpt}$ – Breakpoints

[0 3.5714 7.1429 10.7143 14.2857 17.8571 21.4286 25 28.5714 32.1429 35.7143 39.2857 42.8571 46.4286 50] (default) | array

Engine load breakpoints used for exhaust temperature lookup table, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Speed breakpoints, $f_{t_exh_n_bpt}$ – Breakpoints

[1000 1410.7143 1821.4286 2232.1429 2642.8571 3053.5714 3464.2857 3875 4285.7143 4696.4286 5107.1429 5517.8571 5928.5714 6339.2857 6750] (default) | array

Engine speed breakpoints used for exhaust temperature lookup table, in rpm.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

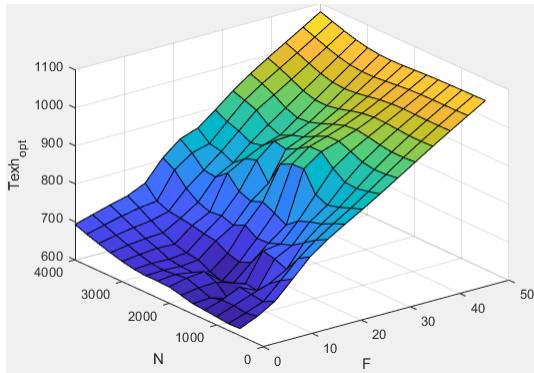
Exhaust Temperature - Torque Structure

Optimal exhaust manifold gas temperature, f_{tqs_exht} – Optimal exhaust manifold gas temperature

array

The optimal exhaust manifold gas temperature lookup table, f_{Texh} , is a function of the engine speed and engine speed and injected fuel mass, $Texh_{opt} = f_{Texh}(F, N)$, where:

- $Texh_{opt}$ is optimal exhaust manifold gas temperature, in K.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



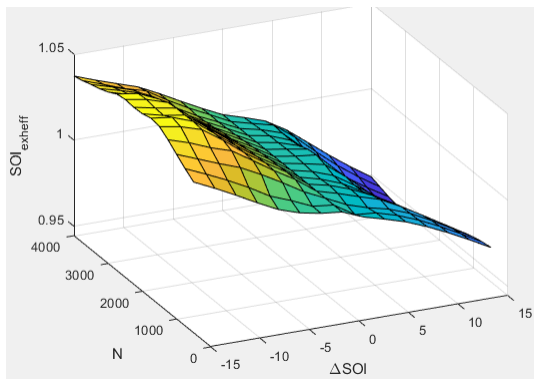
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing exhaust temperature efficiency multiplier, f_tqs_exht_mainsoi_eff – Main SOI timing efficiency multiplier
array

The main start of injection (SOI) timing exhaust temperature efficiency multiplier lookup table, $f_{SOI_{exhteff}}$, is a function of the engine speed engine speed and injected fuel mass, $SOI_{exhteff} = f_{SOI_{exhteff}}(\Delta SOI, N)$, where:

- $SOI_{exhteff}$ is main SOI exhaust temperature efficiency multiplier, dimensionless.
- ΔSOI is main SOI timing relative to optimal timing, in degBTDC.
- N is engine speed, in rpm.



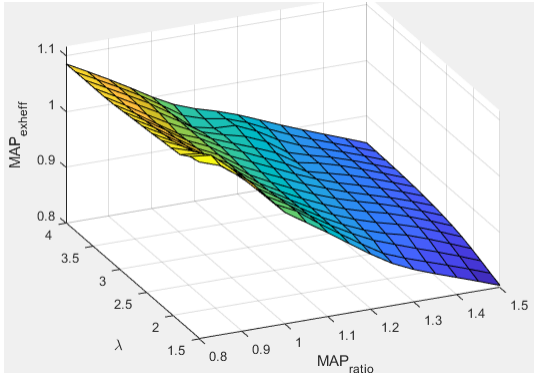
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure exhaust temperature efficiency multiplier, f_tqs_exht_map_eff – Intake manifold efficiency multiplier
array

The intake manifold gas pressure exhaust temperature efficiency multiplier lookup table, $f_{MAP_{exhteff}}$, is a function of the intake manifold gas pressure ratio relative to optimal pressure ratio and lambda, $MAP_{exhteff} = f_{MAP_{exhteff}}(MAP_{ratio}, \lambda)$, where:

- MAP_{exheff} is intake manifold gas pressure exhaust temperature efficiency multiplier, dimensionless.
- MAP_{ratio} is intake manifold gas pressure ratio relative to optimal pressure ratio, dimensionless.
- λ is intake manifold gas lambda, dimensionless.



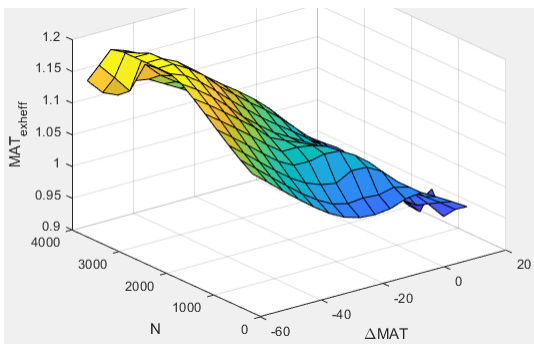
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas temperature exhaust temperature efficiency multiplier, $f_{tqs_exht_mat_eff}$ – Intake manifold efficiency multiplier
array

The intake manifold gas temperature exhaust temperature efficiency multiplier lookup table, $f_{MATexheff}$, is a function of the engine speed and intake manifold gas temperature relative to optimal temperature, $MAT_{exheff} = f_{MATexheff}(\Delta MAT, N)$, where:

- MAT_{exheff} is intake manifold gas temperature exhaust temperature efficiency multiplier, dimensionless.
- ΔMAT is intake manifold gas temperature relative to optimal temperature, in K.
- N is engine speed, in rpm.



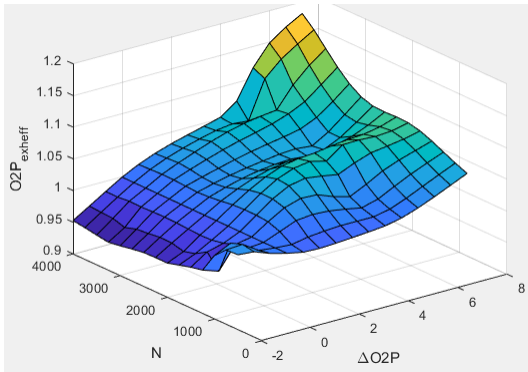
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas oxygen exhaust temperature efficiency multiplier, $f_{tqs_exht_o2pct_eff}$ – Intake manifold efficiency multiplier
array

The intake manifold gas oxygen exhaust temperature efficiency multiplier lookup table, $f_{O2P_{exheff}}$, is a function of the engine speed and intake manifold gas oxygen percent relative to optimal, $O2P_{exheff} = f_{O2P_{exheff}}(\Delta O2P, N)$, where:

- $O2P_{exheff}$ is intake manifold gas oxygen exhaust temperature efficiency multiplier, dimensionless.
- $\Delta O2P$ is intake gas oxygen percent relative to optimal, in percent.
- N is engine speed, in rpm.



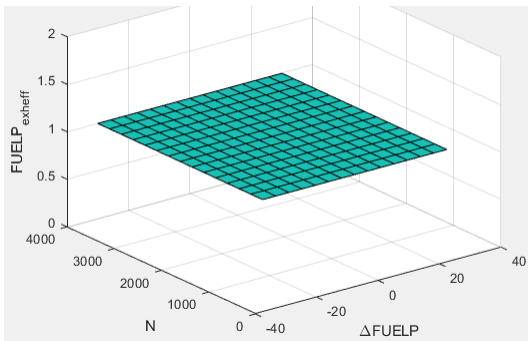
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure exhaust temperature efficiency multiplier, f_tqs_exht_fuelpress_eff – Fuel rail pressure exhaust temperature efficiency multiplier array

The fuel rail pressure efficiency exhaust temperature multiplier lookup table, $f_{FUELP_{exheff}}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $FUELP_{exheff} = f_{FUELP_{exheff}}(\Delta FUELP, N)$, where:

- $FUELP_{exheff}$ is fuel rail pressure exhaust temperature efficiency multiplier, dimensionless.
- $\Delta FUELP$ is fuel rail pressure relative to optimal, in MPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

**Post-injection cylinder wall heat loss transfer coefficient,
f_tqs_exht_post_inj_wall_htc – Post-injection offset**

0 (default) | scalar

Post-injection cylinder wall heat loss transfer coefficient, in W/K.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Version History

Introduced in R2017a

References

[1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

See Also

CI Core Engine | Mapped CI Engine

Topics

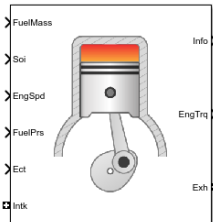
“Engine Calibration Maps”

“Generate Mapped CI Engine from a Spreadsheet”

CI Core Engine

Compression-ignition engine from intake to exhaust port

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Core Engine



Description

The CI Core Engine block implements a compression-ignition (CI) engine from intake to the exhaust port. You can use the block for hardware-in-the-loop (HIL) engine control design or vehicle-level fuel economy and performance simulations.

The CI Core Engine block calculates:

- Brake torque
- Exhaust temperature
- Air-fuel ratio (AFR)
- Fuel rail pressure
- Engine-out (EO) exhaust emissions:
 - Hydrocarbon (HC)
 - Carbon monoxide (CO)
 - Nitric oxide and nitrogen dioxide (NO_x)
 - Carbon dioxide (CO₂)
 - Particulate matter (PM)

Air Mass Flow

To calculate the air mass flow, the compression-ignition (CI) engine uses the “CI Engine Speed-Density Air Mass Flow Model”. The speed-density model uses the speed-density equation to calculate the engine air mass flow, relating the engine intake port mass flow to the intake manifold pressure, intake manifold temperature, and engine speed.

Brake Torque

To calculate the engine torque, you can configure the block to use either of these torque models.

Brake Torque Model	Description
“CI Engine Torque Structure Model”	<p>The CI core engine torque structure model determines the engine torque by reducing the maximum engine torque potential as these engine conditions vary from nominal:</p> <ul style="list-style-type: none"> • Start of injection (SOI) timing • Exhaust back-pressure • Burned fuel mass • Intake manifold gas pressure, temperature, and oxygen percentage • Fuel rail pressure <p>To account for the effect of post-inject fuel on torque, the model uses a calibrated torque offset table.</p>
“CI Engine Simple Torque Model”	<p>For the simple engine torque calculation, the CI engine uses a torque lookup table map that is a function of engine speed and injected fuel mass.</p>

Fuel Flow

In the CI Core Engine and CI Controller blocks, you can represent multiple injections with the start of injection (SOI) and fuel mass inputs to the model. To specify the type of injection, use the **Fuel mass injection type identifier** parameter.

Type of Injection	Parameter Value
Pilot	0
Main	1
Post	2
Passed	3

The model considers Passed fuel injections and fuel injected later than a threshold to be unburned fuel. Use the **Maximum start of injection angle for burned fuel, f_tqs_f_burned_soi_limit** parameter to specify the threshold.

To calculate the engine fuel mass flow, the CI Core Engine block uses fuel mass flow delivered by the injectors and the engine airflow.

$$\dot{m}_{fuel} = \frac{N \cdot N_{cyl}}{Cps \left(\frac{60s}{min} \right) \left(\frac{1000mg}{g} \right)} \sum m_{fuel, inj}$$

To calculate the fuel economy for high-fidelity models, the block uses the volumetric fuel flow.

$$Q_{fuel} = \frac{\dot{m}_{fuel}}{\left(\frac{1000kg}{m^3} \right) Sg_{fuel}}$$

The equation uses these variables.

\dot{m}_{fuel} Fuel mass flow, g/s

$m_{fuel,inj}$	Fuel mass per injection
Cps	Crankshaft revolutions per power stroke, rev/stroke
N_{cyl}	Number of engine cylinders
N	Engine speed, rpm
Q_{fuel}	Volumetric fuel flow
Sg_{fuel}	Specific gravity of fuel

The block uses the internal signal `FlwDir` to track the direction of the flow.

Air-Fuel Ratio

To calculate the air-fuel (AFR) ratio, the CI Core Engine and SI Core Engine blocks implement this equation.

$$AFR = \frac{\dot{m}_{air}}{\dot{m}_{fuel}}$$

The CI Core Engine uses this equation to calculate the relative AFR.

$$\lambda = \frac{AFR}{AFR_s}$$

To calculate the exhaust gas recirculation (EGR), the blocks implement this equation. The calculation expresses the EGR as a percent of the total intake port flow.

$$EGR_{pct} = 100 \frac{\dot{m}_{intk,b}}{\dot{m}_{intk}} = 100 y_{intk,b}$$

The equations use these variables.

AFR	Air-fuel ratio
AFR_s	Stoichiometric air-fuel ratio
\dot{m}_{intk}	Engine air mass flow
\dot{m}_{fuel}	Fuel mass flow
λ	Relative AFR
$y_{intk,b}$	Intake burned mass fraction
EGR_{pct}	EGR percent
$\dot{m}_{intk,b}$	Recirculated burned gas mass flow rate

Exhaust Temperature

The exhaust temperature calculation depends on the torque model. For both torque models, the block implements lookup tables.

Torque Model	Description	Equations
Simple Torque Lookup	Exhaust temperature lookup table is a function of the injected fuel mass and engine speed.	$T_{exh} = f_{Texh}(F, N)$
Torque Structure	<p>The nominal exhaust temperature, $T_{exh_{nom}}$, is a product of these exhaust temperature efficiencies:</p> <ul style="list-style-type: none"> • SOI timing • Intake manifold gas pressure • Intake manifold gas temperature • Intake manifold gas oxygen percentage • Fuel rail pressure • Optimal temperature <p>The exhaust temperature, $T_{exh_{nom}}$, is offset by a post temperature effect, ΔT_{post}, that accounts for post and late injections during the expansion and exhaust strokes.</p>	$T_{exh_{nom}} = SOI_{exh_{teff}} MAP_{exh_{teff}} MAT_{exh_{teff}} O2p_{exh_{teff}} FUEL_{exh_{teff}}$ $T_{exh} = T_{exh_{nom}} + \Delta T_{post}$ $SOI_{exh_{teff}} = f_{SOI_{exh_{teff}}}(\Delta SOI, N)$ $MAP_{exh_{teff}} = f_{MAP_{exh_{teff}}}(MAP_{ratio}, \lambda)$ $MAT_{exh_{teff}} = f_{MAT_{exh_{teff}}}(\Delta MAT, N)$ $O2p_{exh_{teff}} = f_{O2p_{exh_{teff}}}(\Delta O2p, N)$ $Texh_{opt} = f_{Texh}(F, N)$

The equations use these variables.

F	Compression stroke injected fuel mass
N	Engine speed
T_{exh}	Exhaust manifold gas temperature
$T_{exh_{opt}}$	Optimal exhaust manifold gas temperature
ΔT_{post}	Post injection temperature effect
$T_{exh_{nom}}$	Nominal exhaust temperature
$SOI_{exh_{teff}}$	Main SOI exhaust temperature efficiency multiplier
ΔSOI	Main SOI timing relative to optimal timing
$MAP_{exh_{teff}}$	Intake manifold gas pressure exhaust temperature efficiency multiplier
MAP_{ratio}	Intake manifold gas pressure ratio relative to optimal pressure ratio
λ	Intake manifold gas lambda
$MAT_{exh_{teff}}$	Intake manifold gas temperature exhaust temperature efficiency multiplier
ΔMAT	Intake manifold gas temperature relative to optimal temperature
$O2P_{exh_{teff}}$	Intake manifold gas oxygen exhaust temperature efficiency multiplier
$\Delta O2P$	Intake gas oxygen percent relative to optimal
$FUEL_{exh_{teff}}$	Fuel rail pressure exhaust temperature efficiency multiplier
$\Delta FUEL_{P}$	Fuel rail pressure relative to optimal

EO Exhaust Emissions

The block calculates these engine-out (EO) exhaust emissions:

- Hydrocarbon (HC)
- Carbon monoxide (CO)
- Nitric oxide and nitrogen dioxide (NO_x)
- Carbon dioxide (CO₂)
- Particulate matter (PM)

The exhaust temperature determines the specific enthalpy.

$$h_{exh} = Cp_{exh}T_{exh}$$

The exhaust mass flow rate is the sum of the intake port air mass flow and the fuel mass flow.

$$\dot{m}_{exh} = \dot{m}_{intake} + \dot{m}_{fuel}$$

To calculate the exhaust emissions, the block multiplies the emission mass fraction by the exhaust mass flow rate. To determine the emission mass fractions, the block uses lookup tables that are functions of the engine torque and speed.

$$y_{exh,i} = f_{i_frac}(T_{brake}, N)$$

$$\dot{m}_{exh,i} = \dot{m}_{exh}y_{exh,i}$$

The fraction of air and fuel entering the intake port, injected fuel, and stoichiometric AFR determine the air mass fraction that exits the exhaust.

$$y_{exh,air} = \max\left[y_{in,air} - \frac{\dot{m}_{fuel} + y_{in,fuel}\dot{m}_{intake}}{\dot{m}_{fuel} + \dot{m}_{intake}}AFR_s\right]$$

If the engine is operating at the stoichiometric or fuel rich AFR, no air exits the exhaust. Unburned hydrocarbons and burned gas comprise the remainder of the exhaust gas. This equation determines the exhaust burned gas mass fraction.

$$y_{exh,b} = \max[(1 - y_{exh,air} - y_{exh,HC}), 0]$$

The equations use these variables.

T_{exh}	Engine exhaust temperature
h_{exh}	Exhaust manifold inlet-specific enthalpy
Cp_{exh}	Exhaust gas specific heat
\dot{m}_{intk}	Intake port air mass flow rate
\dot{m}_{fuel}	Fuel mass flow rate
\dot{m}_{exh}	Exhaust mass flow rate
$y_{in,fuel}$	Intake fuel mass fraction
$y_{exh,i}$	Exhaust mass fraction for $i = \text{CO}_2, \text{CO}, \text{HC}, \text{NO}_x, \text{air}, \text{burned gas}, \text{and PM}$
$\dot{m}_{exh,i}$	Exhaust mass flow rate for $i = \text{CO}_2, \text{CO}, \text{HC}, \text{NO}_x, \text{air}, \text{burned gas}, \text{and PM}$

T_{brake}	Engine brake torque
N	Engine speed
$y_{exh,air}$	Exhaust air mass fraction
$y_{exh,b}$	Exhaust air burned mass fraction

Power Accounting

For the power accounting, the block implements equations that depend on **Torque model**.

When you set **Torque model** to Simple Torque Lookup, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrIntkHeatFlw	Intake heat flow $\dot{m}_{intk}h_{intk}$
		PwrExhHeatFlw	Exhaust heat flow $-\dot{m}_{exh}h_{exh}$
		PwrCrkshft	Crankshaft power $-T_{brake}\omega$
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrFuel	Fuel input power $\dot{m}_{fuel}LHV$	
	PwrLoss	All losses $T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh}$	

Bus Signal		Description	Equations
	<p>PwrStored</p> <p>— Stored energy rate of change</p> <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	Not used	

When you set **Torque model** to Torque Structure, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	<p>PwrTrnsfrd</p> <p>— Power transferred between blocks</p> <ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrIntkHeatFlw	Intake heat flow $\dot{m}_{intk}h_{intk}$
		PwrExhHeatFlw	Exhaust heat flow $-\dot{m}_{exh}h_{exh}$
		PwrCrkshft	Crankshaft power $-T_{brake}\omega$
	<p>PwrNotTrnsfrd</p> <p>— Power crossing the block boundary, but not transferred</p> <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrFuel	Fuel input power $\dot{m}_{fuel}LHV$
		PwrFricLoss	Friction loss $-T_{fric}\omega$
		PwrPumpLoss	Pumping loss $-T_{pump}\omega$
		PwrHeatLoss	Heat transfer loss $T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh} + T_{fric}\omega + T_{pump}\omega$

Bus Signal	Description	Equations
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	<i>Not used</i>	

h_{exh}	Exhaust manifold inlet-specific enthalpy
h_{intk}	Intake port specific enthalpy
\dot{m}_{intk}	Intake port air mass flow rate
\dot{m}_{fuel}	Fuel mass flow rate
\dot{m}_{exh}	Exhaust mass flow rate
ω	Engine speed
T_{brake}	Brake torque
T_{pump}	Engine pumping work offset to inner torque
T_{fric}	Engine friction torque
LHV	Fuel lower heating value

Ports

Input

FuelMass — Fuel injector pulse-width

vector

Fuel mass per injection, $m_{fuel,inj}$, in mg per injection.

Soi — Start of fuel injection timing

vector

Fuel injection timing, SOI , in degrees crank angle after top dead center (degATDC). First vector value, $Soi(1)$, is main injection timing.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

EngSpd — Engine speed

scalar

Engine speed, N , in rpm.

FuelPrs — Fuel rail pressure

scalar

Fuel rail pressure, $FUELP$, in MPa.**Dependencies**To enable this parameter, for **Torque model**, select Torque Structure.**Ect — Engine cooling temperature**

scalar

Engine cooling temperature, $T_{coolant}$, in K.**Dependencies**To enable this parameter, for **Torque model**, select Torque Structure.**Intk — Intake port pressure, temperature, enthalpy, mass fractions**

two-way connector port

Bus containing the upstream:

- Prs — Pressure, in Pa
- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Intake port mass fractions, dimensionless. Exhaust gas recirculation (EGR) mass flow at the intake port is burned gas.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Exh — Exhaust port pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the exhaust:

- Prs — Pressure, in Pa

- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Exhaust port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable	Units
IntkGasMassFlw	Engine intake air mass flow.	\dot{m}_{air}	kg/s
IntkAirMassFlw	Engine intake port mass flow.	\dot{m}_{intk}	kg/s
NrmlzdAirChrg	Engine load (that is, normalized cylinder air mass) corrected for final steady-state cam phase angles	L	N/A
Afr	Air-fuel ratio at engine exhaust port	AFR	N/A
FuelMassFlw	Fuel flow into engine	\dot{m}_{fuel}	kg/s
FuelVolFlw	Volumetric fuel flow	Q_{fuel}	m ³ /s
ExhManGasTemp	Exhaust gas temperature at exhaust manifold inlet	T_{exh}	K
EngTrq	Engine brake torque	T_{brake}	N·m
EngSpd	Engine speed	N	rpm

Signal		Description	Variable	Units	
IntkCamPhase		Intake cam phaser angle	φ_{ICP}	degrees crank advance	
ExhCamPhase		Exhaust cam phaser angle	φ_{ECP}	degrees crank retard	
CrkAng		Engine crankshaft absolute angle	$\int_0^{(360)Cps} EngSpd \frac{180}{30} d\theta$ where <i>Cps</i> is crankshaft revolutions per power stroke	degrees crank angle	
EgrPct		EGR percent	EGR_{pct}	N/A	
EoAir		EO air mass flow rate	\dot{m}_{exh}	kg/s	
EoBrndGas		EO burned gas mass flow rate	$y_{exh,b}$	kg/s	
EoHC		EO hydrocarbon emission mass flow rate	$y_{exh,HC}$	kg/s	
EoCO		EO carbon monoxide emission mass flow rate	$y_{exh,CO}$	kg/s	
EoNOx		EO nitric oxide and nitrogen dioxide emissions mass flow rate	$y_{exh,NOx}$	kg/s	
EoCO2		EO carbon dioxide emission mass flow rate	$y_{exh,CO2}$	kg/s	
EoPm		EO particulate matter emission mass flow rate	$y_{exh,PM}$	kg/s	
PwrInfo	PwrTrnsfrd	PwrIntkHeatFlw	Intake heat flow	$\dot{m}_{intk}h_{intk}$	W
		PwrExhHeatFlw	Exhaust heat flow	$-\dot{m}_{exh}h_{exh}$	W
		PwrCrkshft	Crankshaft power	$-T_{brake}\omega$	W
	PwrNotTrnsfrd	PwrFuel	Fuel input power	$\dot{m}_{fuel}LHV$	W
		PwrLoss	For Torque model set to Simple Torque Lookup: All losses	$T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh}$	W
		PwrFricLoss	For Torque model set to Torque Structure: Friction loss	$-T_{fric}\omega$	W

Signal		Description	Variable	Units
	PwrPumpLoss	For Torque model set to Torque Structure: Pumping loss	$-T_{pump}\omega$	W
	PwrHeatTransferLoss	For Torque model set to Torque Structure: Heat transfer loss	$T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh} + T_{fric}\omega + T_{pump}\omega$	W
	PwrStored	<i>Not used</i>		

EngTrq – Engine brake torque

scalar

Engine brake torque, T_{brake} , in N·m.**Intk – Intake port mass flow rate, heat flow rate, temperature, mass fraction**

two-way connector port

Bus containing:

- MassFlwRate – Intake port mass flow rate, in kg/s
- HeatFlwRate – Intake port heat flow rate, in J/s
- ExhManGasTemp – Intake port temperature, in K
- MassFrac – Intake port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac – Oxygen
- N2MassFrac – Nitrogen
- UnbrndFuelMassFrac – Unburned fuel
- CO2MassFrac – Carbon dioxide
- H2OMassFrac – Water
- COMassFrac – Carbon monoxide
- NOMassFrac – Nitric oxide
- NO2MassFrac – Nitrogen dioxide
- NOxMassFrac – Nitric oxide and nitrogen dioxide
- PmMassFrac – Particulate matter
- AirMassFrac – Air
- BrndGasMassFrac – Burned gas

Exh – Exhaust port mass flow rate, heat flow rate, temperature, mass fraction

two-way connector port

Bus containing:

- MassFlwRate – Exhaust port mass flow rate, in kg/s

- HeatFlwRate — Exhaust heat flow rate, in J/s
- ExhManGasTemp — Exhaust port temperature, in K
- MassFrac — Exhaust port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Parameters

Block Options

Torque model — Select torque model

Torque Structure (default) | Simple Torque Lookup

To calculate the engine torque, you can configure the block to use either of these torque models.

Brake Torque Model	Description
“CI Engine Torque Structure Model”	<p>The CI core engine torque structure model determines the engine torque by reducing the maximum engine torque potential as these engine conditions vary from nominal:</p> <ul style="list-style-type: none"> • Start of injection (SOI) timing • Exhaust back-pressure • Burned fuel mass • Intake manifold gas pressure, temperature, and oxygen percentage • Fuel rail pressure <p>To account for the effect of post-inject fuel on torque, the model uses a calibrated torque offset table.</p>
“CI Engine Simple Torque Model”	<p>For the simple engine torque calculation, the CI engine uses a torque lookup table map that is a function of engine speed and injected fuel mass.</p>

Air**Number of cylinders, NCyl – Engine cylinders**

4 (default) | scalar

Number of engine cylinders, N_{cyl} .**Air standard temperature, Pstd – Temperature**

293.15 (default) | scalar

Standard air temperature, T_{std} , in K.**Crank revolutions per power stroke, Cps – Revolutions per stroke**

2 (default) | scalar

Crankshaft revolutions per power stroke, Cps , in rev/stroke.**Total displaced volume, Vd – Volume**

0.0015 (default) | scalar

Displaced volume, V_d , in m^3 .**Ideal gas constant air, Rair – Constant**

287.05 (default) | scalar

Ideal gas constant, R_{air} , in $J/(kg \cdot K)$.**Air standard pressure, Pstd – Pressure**

101325 (default) | scalar

Standard air pressure, P_{std} , in Pa.**Speed-density volumetric efficiency, f_nv – Lookup table**

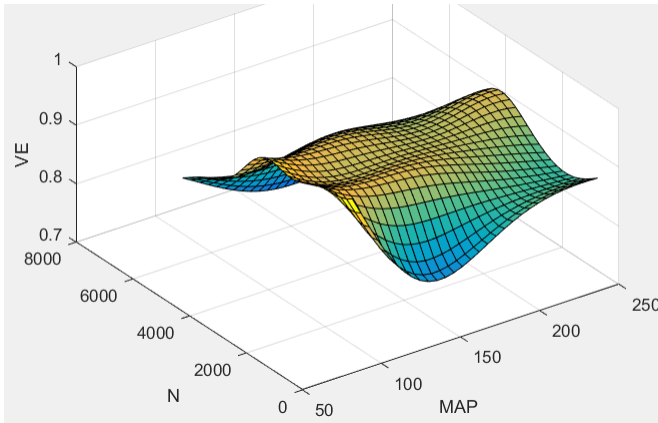
array

The volumetric efficiency lookup table is a function of the intake manifold absolute pressure at intake valve closing (IVC) and engine speed

$$\eta_v = f_{\eta_v}(MAP, N)$$

where:

- η_v is engine volumetric efficiency, dimensionless.
- MAP is intake manifold absolute pressure, in KPa.
- N is engine speed, in rpm.



Speed-density intake manifold pressure breakpoints, $f_{nv_prs_bpt}$ – Breakpoints vector

Intake manifold pressure breakpoints for speed-density volumetric efficiency lookup table, in KPa.

Speed-density engine speed breakpoints, $f_{nv_n_bpt}$ – Breakpoints vector

Engine speed breakpoints for speed-density volumetric efficiency lookup table, in rpm.

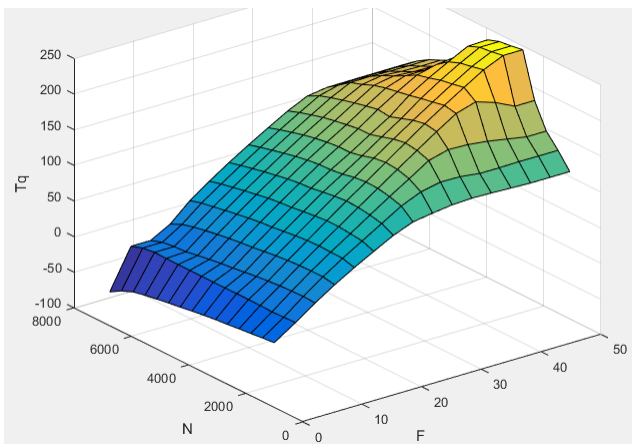
Torque

Torque - Simple Torque Lookup

Torque table, f_{tq_nf} – Lookup table array

For the simple torque lookup table model, the CI engine uses a lookup table is a function of engine speed and injected fuel mass, $T_{brake} = f_{Tnf}(F, N)$, where:

- $Tq = T_{brake}$ is engine brake torque after accounting for engine mechanical and pumping friction effects, in N·m.
- F is injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque table fuel mass per injection breakpoints, f_tq_nf_f_bpt – Breakpoints

[0 3.5714 7.1429 10.7143 14.2857 17.8571 21.4286 25 28.5714 32.1429 35.7143 39.2857 42.8571 46.4286 50] (default) | vector

Torque table fuel mass per injection breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque table speed breakpoints, f_tq_nf_n_bpt – Breakpoints

[1000 1410.7143 1821.4286 2232.1429 2642.8571 3053.5714 3464.2857 3875 4285.7143 4696.4286 5107.1429 5517.8571 5928.5714 6339.2857 6750] (default) | vector

Engine speed breakpoints, in rpm.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Torque - Torque Structure**Fuel mass per injection breakpoints, f_tqs_f_bpt – Breakpoints**

vector

Fuel mass per injection breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Engine speed breakpoints, f_tqs_n_bpt – Breakpoints

[500 750 1000 1250 1500 1750 2000 2250 2500 2750 3000 3250 3500 3750 4000] (default) | vector

Engine speed breakpoints, in rpm.

Dependencies

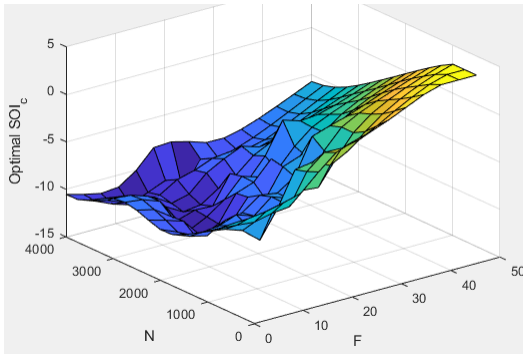
To enable this parameter, for **Torque model**, select Torque Structure.

Optimal main start of injection timing, f_tqs_mainsoi – Optimal MAINSOI

array

The optimal main start of injection (SOI) timing lookup table, f_{SOI_c} , is a function of the engine speed and injected fuel mass, $SOI_c = f_{SOI_c}(F, N)$, where:

- SOI_c is optimal SOI timing, in degATDC.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



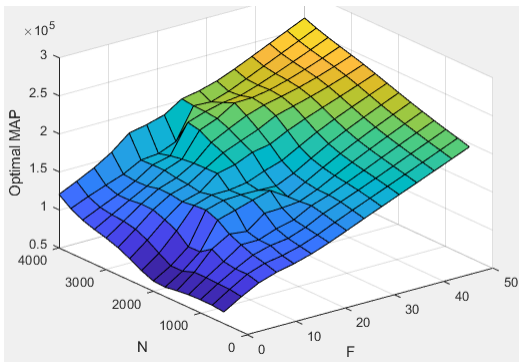
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake manifold gas pressure, f_tqs_map – Optimal intake MAP
array

The optimal intake manifold gas pressure lookup table, f_{MAP} , is a function of the engine speed and injected fuel mass, $MAP = f_{MAP}(F, N)$, where:

- MAP is optimal intake manifold gas pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



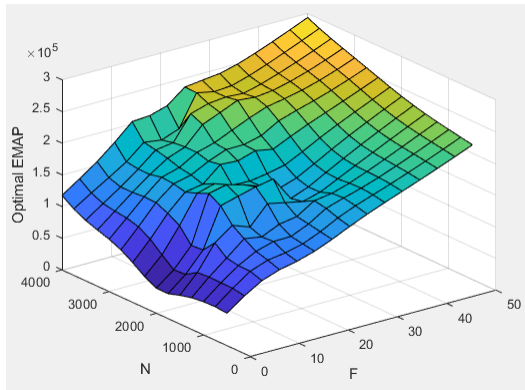
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal exhaust manifold gas pressure, f_tqs_emap – Optimal exhaust MAP
array

The optimal exhaust manifold gas pressure lookup table, f_{EMAP} , is a function of the engine speed and injected fuel mass, $EMAP = f_{EMAP}(F, N)$, where:

- $EMAP$ is optimal exhaust manifold gas pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



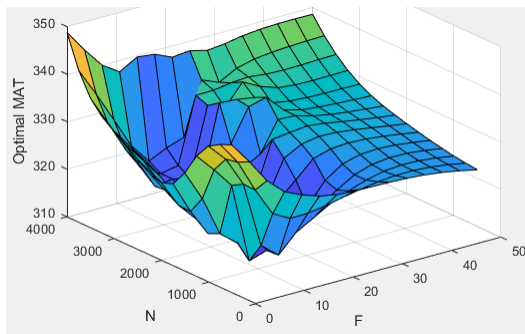
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake manifold gas temperature, f_{tqs_mat} – Optimal intake MAT array

The optimal intake manifold gas temperature lookup table, f_{MAT} , is a function of the engine speed and injected fuel mass, $MAT = f_{MAT}(F, N)$, where:

- MAT is optimal intake manifold gas temperature, in K.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



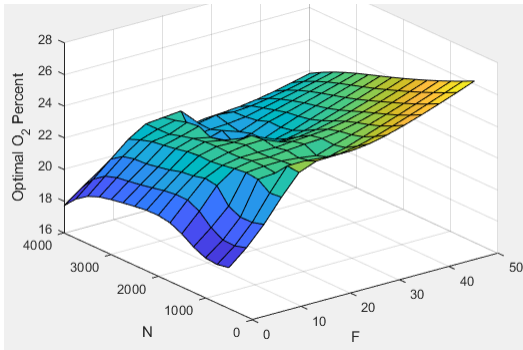
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal intake gas oxygen percent, f_{tqs_o2pct} – Optimal intake gas oxygen array

The optimal intake gas oxygen percent lookup table, f_{O_2} , is a function of the engine speed and injected fuel mass, $O2PCT = f_{O_2}(F, N)$, where:

- $O2PCT$ is optimal intake gas oxygen, in percent.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



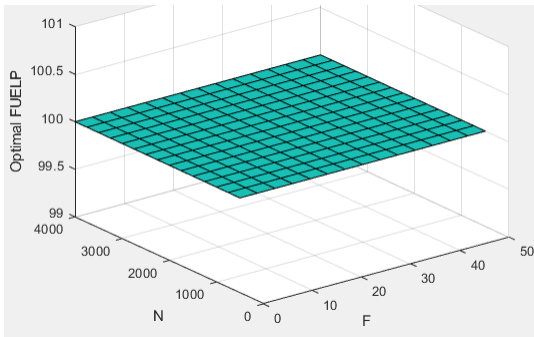
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal fuel rail pressure, f_tqs_fuelpress – Optimal fuel rail pressure array

The optimal fuel rail pressure lookup table, f_{fuelp} , is a function of the engine speed and injected fuel mass, $FUELP = f_{fuelp}(F,N)$, where:

- $FUELP$ is optimal fuel rail pressure, in MPa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



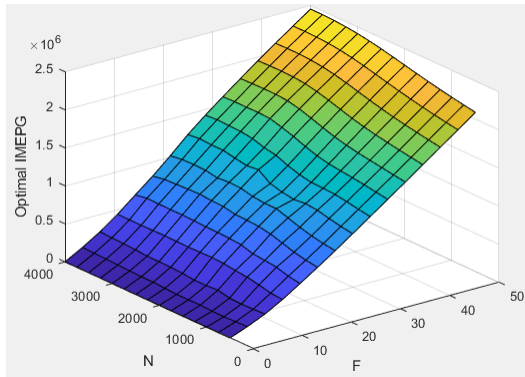
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal gross indicated mean effective pressure, f_tqs_imepg – Optimal mean effective pressure array

The optimal gross indicated mean effective pressure lookup table, f_{imepg} , is a function of the engine speed and injected fuel mass, $IMEPG = f_{imepg}(F,N)$, where:

- $IMEPG$ is optimal gross indicated mean effective pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



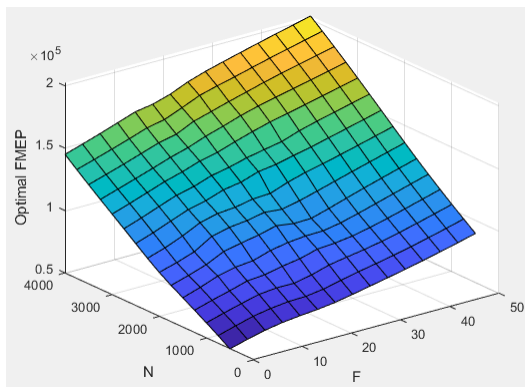
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Optimal friction mean effective pressure, f_{tqs_fmep} – Optimal friction mean effective pressure
array

The optimal friction mean effective pressure lookup table, f_{fmep} , is a function of the engine speed and injected fuel mass, $FMEP = f_{fmep}(F, N)$, where:

- $FMEP$ is optimal friction mean effective pressure, in Pa.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

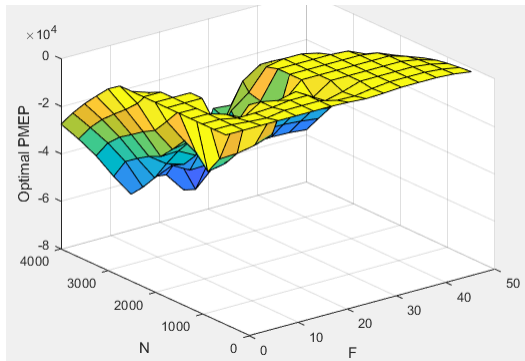
To enable this parameter, for **Torque model**, select Torque Structure.

Optimal pumping mean effective pressure, f_{tqs_pmep} – Optimal pumping mean effective pressure
array

The optimal pumping mean effective pressure lookup table, f_{pmep} , is a function of the engine speed and injected fuel mass, $PMEP = f_{pmep}(F, N)$, where:

- $PMEP$ is optimal pumping mean effective pressure, in Pa.

- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Friction multiplier as a function of temperature, f_tqs_fric_temp_mod – Friction multiplier

array

Friction multiplier as a function of temperature, dimensionless.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Friction multiplier temperature breakpoints, f_tqs_fric_temp_bpt – Breakpoints

vector

Friction multiplier temperature breakpoints, in K.

Dependencies

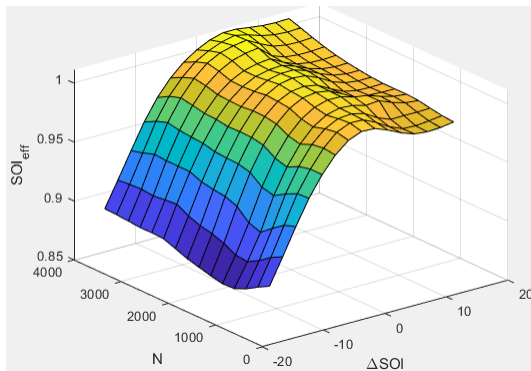
To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing efficiency multiplier, f_tqs_mainsoi_eff – MAINSOI efficiency multiplier

array

The main start of injection (SOI) timing efficiency multiplier lookup table, $f_{SOI_{eff}}$, is a function of the engine speed and main SOI timing relative to optimal timing, $SOI_{eff} = f_{SOI_{eff}}(\Delta SOI, N)$, where:

- SOI_{eff} is main SOI timing efficiency multiplier, dimensionless.
- ΔSOI is main SOI timing relative to optimal timing, in degBTDC.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing relative to optimal timing breakpoints, f_tqs_mainsoi_delta_bpt – Breakpoints
vector

Main start of injection timing relative to optimal timing breakpoints, in degBTDC.

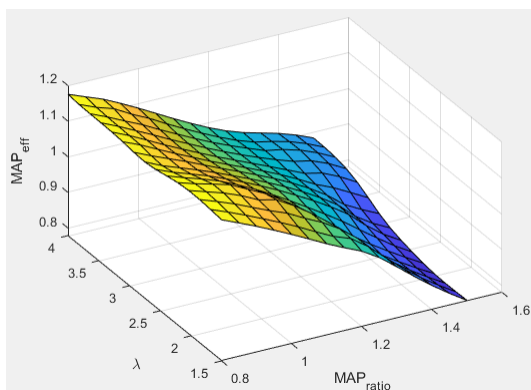
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure efficiency multiplier, f_tqs_map_eff – Intake pressure efficiency multiplier
array

The intake manifold gas pressure efficiency multiplier lookup table, $f_{MAP_{eff}}$, is a function of the intake manifold gas pressure ratio relative to optimal pressure ratio and lambda, $MAP_{eff} = f_{MAP_{eff}}(MAP_{ratio}, \lambda)$, where:

- MAP_{eff} is intake manifold gas pressure efficiency multiplier, dimensionless.
- MAP_{ratio} is intake manifold gas pressure ratio relative to optimal pressure ratio, dimensionless.
- λ is intake manifold gas lambda, dimensionless.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure ratio relative to optimal pressure ratio breakpoints, $f_{tqs_map_ratio_bpt}$ — Breakpoints

[0.8;0.85;0.9;0.95;1;1.05;1.1;1.15;1.2;1.25;1.3;1.35;1.4;1.45;1.5] (default) | vector

Intake manifold gas pressure ratio relative to optimal pressure ratio breakpoints, dimensionless.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas lambda breakpoints, $f_{tqs_lambda_bpt}$ — Breakpoints

[1.5 1.678571428571429 1.857142857142857 2.035714285714286 2.214285714285714 2.392857142857143 2.571428571428571 2.75 2.928571428571429 3.107142857142857 3.285714285714286 3.464285714285714 3.642857142857143 3.821428571428572 4] (default) | vector

Intake manifold gas lambda breakpoints, dimensionless.

Dependencies

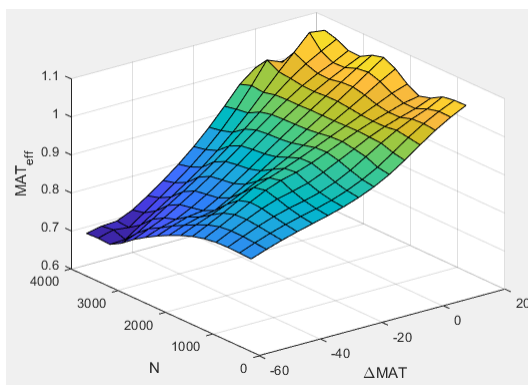
To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas temperature efficiency multiplier, $f_{tqs_mat_eff}$ — Intake temperature efficiency multiplier

array

The intake manifold gas temperature efficiency multiplier lookup table, $f_{MAT_{eff}}$, is a function of the engine speed and intake manifold gas temperature relative to optimal temperature, $MAT_{eff} = f_{MAT_{eff}}(\Delta MAT, N)$, where:

- MAT_{eff} is intake manifold gas temperature efficiency multiplier, dimensionless.
- ΔMAT is intake manifold gas temperature relative to optimal temperature, in K.
- N is engine speed, in rpm.

**Dependencies**

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas temperature relative to optimal gas temperature breakpoints, $f_{tqs_mat_delta_bpt}$ — Breakpoints

[-55; -50; -45; -40; -35; -30; -25; -20; -15; -10; -5; 0; 5; 10; 15] (default) | vector

Intake manifold gas temperature relative to optimal gas temperature breakpoints, in K.

Dependencies

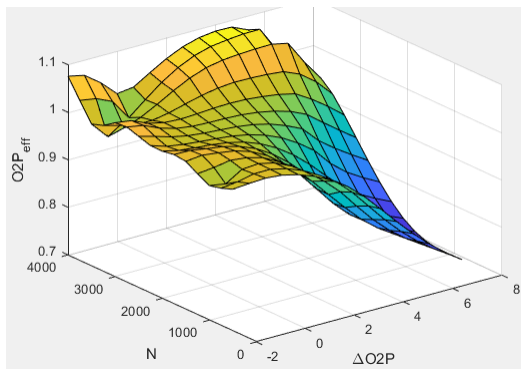
To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas oxygen efficiency multiplier, $f_{tqs_o2pct_eff}$ – Intake oxygen efficiency multiplier

array

The intake manifold gas oxygen efficiency multiplier lookup table, $f_{O2P_{eff}}$, is a function of the engine speed and intake manifold gas oxygen percent relative to optimal, $O2P_{eff} = f_{O2P_{eff}}(\Delta O2P, N)$, where:

- $O2P_{eff}$ is intake manifold gas oxygen efficiency multiplier, dimensionless.
- $\Delta O2P$ is intake gas oxygen percent relative to optimal, in percent.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake gas oxygen percent relative to optimal breakpoints, $f_{tqs_o2pct_delta_bpt}$ – Breakpoints

vector

Intake gas oxygen percent relative to optimal breakpoints, in percent.

Dependencies

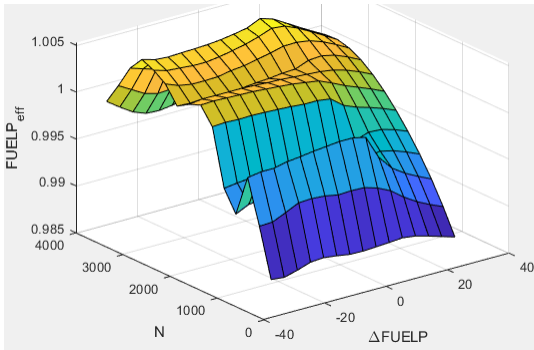
To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure efficiency multiplier, $f_{tqs_fuelpress_eff}$ – Efficiency multiplier

array

The fuel rail pressure efficiency multiplier lookup table, $f_{FUELPeff}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $FUELPeff = f_{FUELPeff}(\Delta FUELPeff, N)$, where:

- $FUELPeff$ is fuel rail pressure efficiency multiplier, dimensionless.
- $\Delta FUELPeff$ is fuel rail pressure relative to optimal, in MPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure relative to optimal breakpoints, f_tqs_fuelpress_delta_bpt – Breakpoints
vector

Fuel rail pressure relative to optimal breakpoints, in MPa.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel mass injection type identifier, f_tqs_f_inj_type – Type identifier
0 (default) | scalar

Fuel mass injection type identifier, dimensionless.

In the CI Core Engine and CI Controller blocks, you can represent multiple injections with the start of injection (SOI) and fuel mass inputs to the model. To specify the type of injection, use the **Fuel mass injection type identifier** parameter.

Type of Injection	Parameter Value
Pilot	0
Main	1
Post	2
Passed	3

The model considers Passed fuel injections and fuel injected later than a threshold to be unburned fuel. Use the **Maximum start of injection angle for burned fuel, f_tqs_f_burned_soi_limit** parameter to specify the threshold.

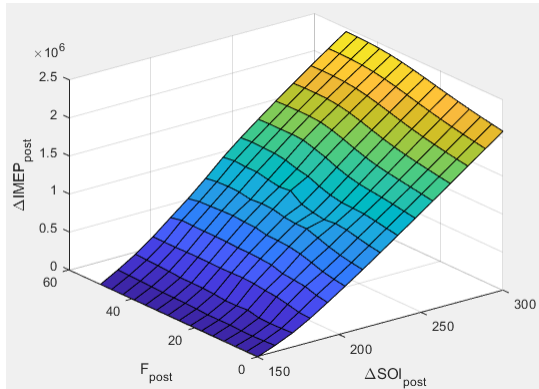
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject correction, f_tqs_imep_post_corr – Post inject correction
array

The indicated mean effective pressure post inject correction lookup table, $f_{IMEP_{post}}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $\Delta IMEP_{post} = f_{IMEP_{post}}(\Delta SOI_{post}, F_{post})$, where:

- $\Delta IMEP_{post}$ is indicated mean effective pressure post inject correction, in Pa.
- ΔSOI_{post} is indicated mean effective pressure post inject start of inject timing centroid, in degATDC.
- F_{post} is indicated mean effective pressure post inject mass sum, in mg per injection.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject mass sum breakpoints, **f_tqs_f_post_sum_bpt** – Breakpoints

```
[0 3.571428571428572 7.142857142857143 10.71428571428571 14.28571428571429
17.85714285714286 21.42857142857143 25 28.57142857142857 32.14285714285715
35.71428571428572 39.28571428571428 42.85714285714285 46.42857142857143 50]
(default) | vector
```

Indicated mean effective pressure post inject mass sum breakpoints, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Indicated mean effective pressure post inject start of inject timing centroid breakpoints, **f_tqs_soi_post_cent_bpt** – Breakpoints

```
[150 160.7142857142857 171.4285714285714 182.1428571428571 192.8571428571429
203.5714285714286 214.2857142857143 225 235.7142857142857 246.4285714285714
257.1428571428571 267.8571428571429 278.5714285714286 289.2857142857143 300]
(default) | vector
```

Indicated mean effective pressure post inject start of inject timing centroid breakpoints, in degATDC.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Maximum start of injection angle for burned fuel, **f_tqs_f_burned_soi_limit** – Maximum SOI angle for burned fuel

```
500 (default) | scalar
```

Maximum start of injection angle for burned fuel, in degATDC.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Exhaust

Exhaust Temperature - Simple Torque Lookup

Exhaust temperature table, f_t_exh – Lookup table

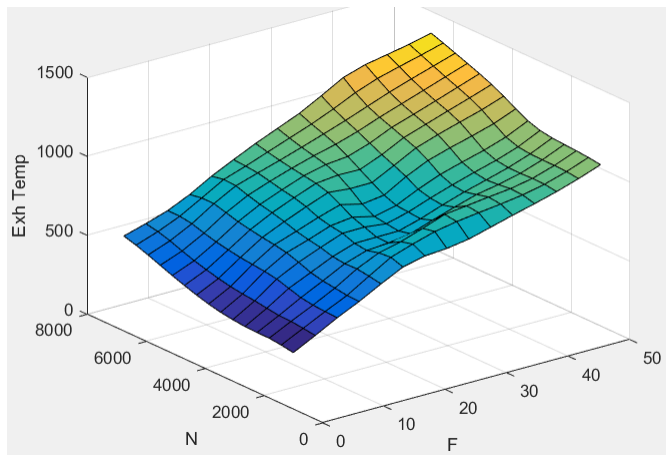
array

The lookup table for the exhaust temperature is a function of injected fuel mass and engine speed

$$T_{exh} = f_{Texh}(F, N)$$

where:

- T_{exh} is exhaust temperature, in K.
- F is injected fuel mass, in mg per injection.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Fuel mass per injection breakpoints, f_t_exh_f_bpt – Breakpoints

[0 3.5714 7.1429 10.7143 14.2857 17.8571 21.4286 25 28.5714 32.1429 35.7143 39.2857 42.8571 46.4286 50] (default) | array

Engine load breakpoints used for exhaust temperature lookup table, in mg per injection.

Dependencies

To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Speed breakpoints, $f_t_exh_n_bpt$ – Breakpoints

[1000 1410.7143 1821.4286 2232.1429 2642.8571 3053.5714 3464.2857 3875
4285.7143 4696.4286 5107.1429 5517.8571 5928.5714 6339.2857 6750] (default) |
array

Engine speed breakpoints used for exhaust temperature lookup table, in rpm.

Dependencies

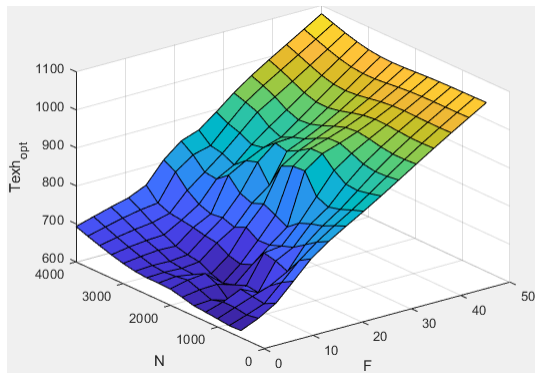
To enable this parameter, for **Torque model**, select Simple Torque Lookup.

Exhaust Temperature - Torque Structure**Optimal exhaust manifold gas temperature, f_tqs_exht – Optimal exhaust manifold gas temperature**

array

The optimal exhaust manifold gas temperature lookup table, f_{Texh} , is a function of the engine speed engine speed and injected fuel mass, $Texh_{opt} = f_{Texh}(F, N)$, where:

- $Texh_{opt}$ is optimal exhaust manifold gas temperature, in K.
- F is compression stroke injected fuel mass, in mg per injection.
- N is engine speed, in rpm.

**Dependencies**

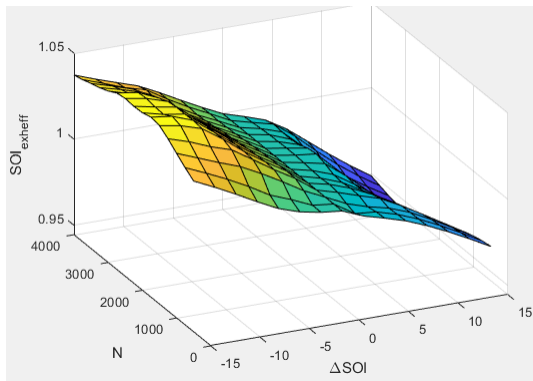
To enable this parameter, for **Torque model**, select Torque Structure.

Main start of injection timing exhaust temperature efficiency multiplier, $f_tqs_exht_mainsoi_eff$ – Main SOI timing efficiency multiplier

array

The main start of injection (SOI) timing exhaust temperature efficiency multiplier lookup table, $f_{SOIexhteff}$, is a function of the engine speed engine speed and injected fuel mass, $SOI_{exhteff} = f_{SOIexhteff}(\Delta SOI, N)$, where:

- $SOI_{exhteff}$ is main SOI exhaust temperature efficiency multiplier, dimensionless.
- ΔSOI is main SOI timing relative to optimal timing, in degBTDC.
- N is engine speed, in rpm.



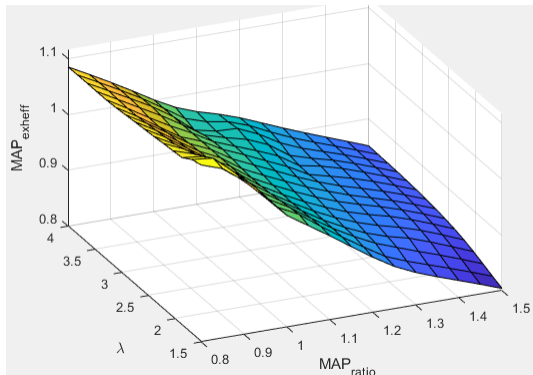
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas pressure exhaust temperature efficiency multiplier, f_tqs_exht_map_eff – Intake manifold efficiency multiplier
array

The intake manifold gas pressure exhaust temperature efficiency multiplier lookup table, $f_{MAPexheff}$, is a function of the intake manifold gas pressure ratio relative to optimal pressure ratio and lambda, $MAP_{exheff} = f_{MAPexheff}(MAP_{ratio}, \lambda)$, where:

- MAP_{exheff} is intake manifold gas pressure exhaust temperature efficiency multiplier, dimensionless.
- MAP_{ratio} is intake manifold gas pressure ratio relative to optimal pressure ratio, dimensionless.
- λ is intake manifold gas lambda, dimensionless.



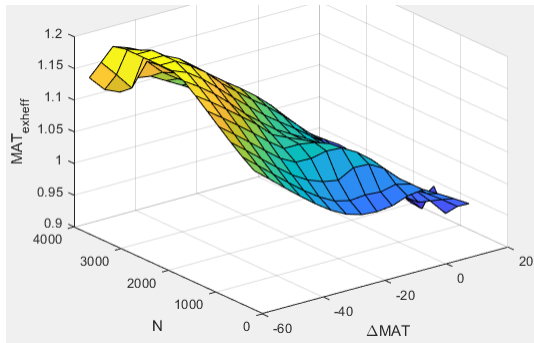
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas temperature exhaust temperature efficiency multiplier, f_tqs_exht_mat_eff – Intake manifold efficiency multiplier
array

The intake manifold gas temperature exhaust temperature efficiency multiplier lookup table, $f_{MATexheff}$, is a function of the engine speed and intake manifold gas temperature relative to optimal temperature, $MAT_{exheff} = f_{MATexheff}(\Delta MAT, N)$, where:

- MAT_{exheff} is intake manifold gas temperature exhaust temperature efficiency multiplier, dimensionless.
- ΔMAT is intake manifold gas temperature relative to optimal temperature, in K.
- N is engine speed, in rpm.



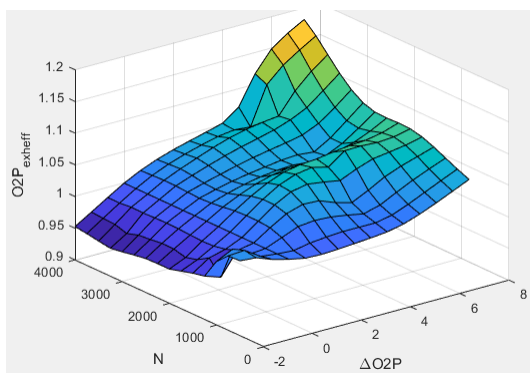
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intake manifold gas oxygen exhaust temperature efficiency multiplier, $f_{tqs_exht_o2pct_eff}$ – Intake manifold efficiency multiplier
array

The intake manifold gas oxygen exhaust temperature efficiency multiplier lookup table, $f_{O2Pexheff}$, is a function of the engine speed and intake manifold gas oxygen percent relative to optimal, $O2P_{exheff} = f_{O2Pexheff}(\Delta O2P, N)$, where:

- $O2P_{exheff}$ is intake manifold gas oxygen exhaust temperature efficiency multiplier, dimensionless.
- $\Delta O2P$ is intake gas oxygen percent relative to optimal, in percent.
- N is engine speed, in rpm.



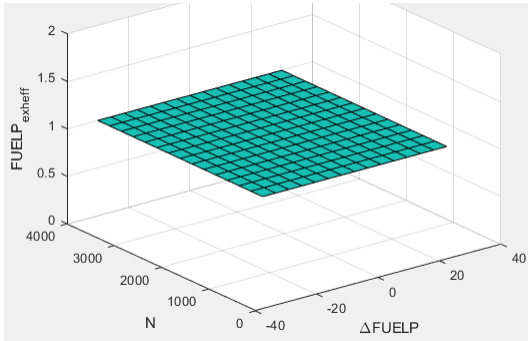
Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Fuel rail pressure exhaust temperature efficiency multiplier, $f_{tqs_exht_fuelpress_eff}$ – Fuel rail pressure exhaust temperature efficiency multiplier
array

The fuel rail pressure efficiency exhaust temperature multiplier lookup table, $f_{FUELP_{exheff}}$, is a function of the engine speed and fuel rail pressure relative to optimal breakpoints, $FUELP_{exheff} = f_{FUELP_{exheff}}(\Delta FUELP, N)$, where:

- $FUELP_{exheff}$ is fuel rail pressure exhaust temperature efficiency multiplier, dimensionless.
- $\Delta FUELP$ is fuel rail pressure relative to optimal, in MPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Post-injection cylinder wall heat loss transfer coefficient, $f_{tqs_exht_post_inj_wall_htc}$ – Post-injection offset

0 (default) | scalar

Post-injection cylinder wall heat loss transfer coefficient, in W/K.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

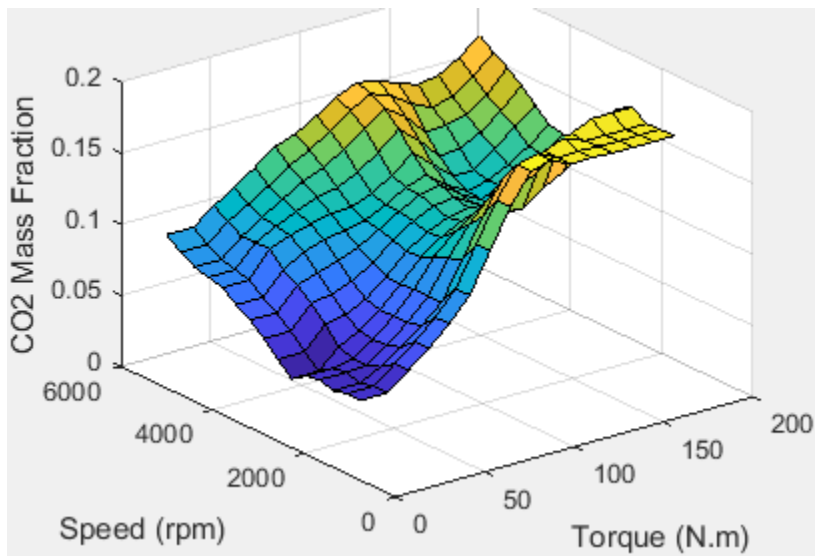
Emissions

CO₂ mass fraction table, $f_{CO_2_frac}$ – Carbon dioxide (CO₂) emission lookup table

array

The CI Core Engine CO₂ emission mass fraction lookup table is a function of engine torque and engine speed, $CO_2\ Mass\ Fraction = f(Speed, Torque)$, where:

- $CO_2\ Mass\ Fraction$ is the CO₂ emission mass fraction, dimensionless.
- $Speed$ is engine speed, in rpm.
- $Torque$ is engine torque, in N·m.



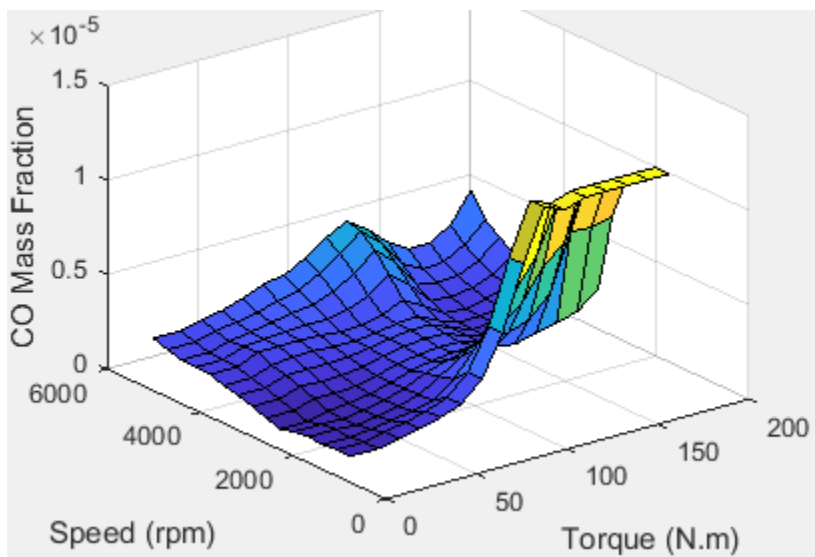
Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO2**.

CO mass fraction table, f_{CO_frac} – Carbon monoxide (CO) emission lookup table array

The CI Core Engine CO emission mass fraction lookup table is a function of engine torque and engine speed, $CO\ Mass\ Fraction = f(Speed, Torque)$, where:

- *CO Mass Fraction* is the CO emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



Dependencies

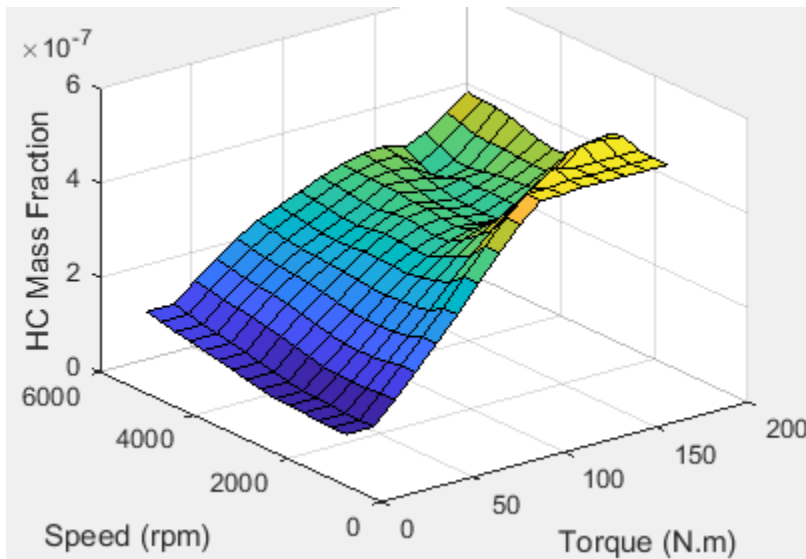
To enable this parameter, on the **Exhaust** tab, select **CO**.

HC mass fraction table, f_HC_frac – Hydrocarbon (HC) emission lookup table

array

The CI Core Engine HC emission mass fraction lookup table is a function of engine torque and engine speed, $HC\ Mass\ Fraction = f(Speed, Torque)$, where:

- *HC Mass Fraction* is the HC emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.

**Dependencies**

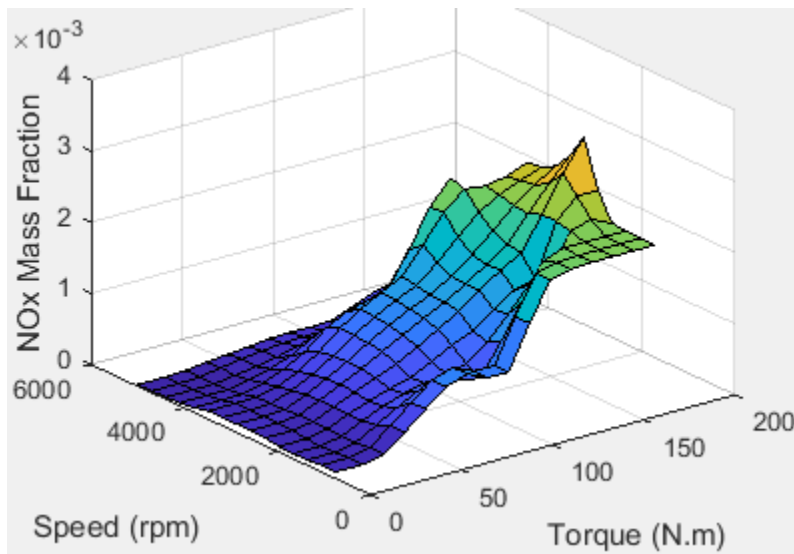
To enable this parameter, on the **Exhaust** tab, select **HC**.

NOx mass fraction table, f_NOx_frac – Nitric oxide and nitrogen dioxide (NOx) emission lookup table

array

The CI Core Engine NOx emission mass fraction lookup table is a function of engine torque and engine speed, $NOx\ Mass\ Fraction = f(Speed, Torque)$, where:

- *NOx Mass Fraction* is the NOx emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



Dependencies

To enable this parameter, on the **Exhaust** tab, select **NOx**.

PM mass fraction table, `f_PM_frac` – Particulate matter (PM) emission lookup table array

The CI Core Engine PM emission mass fraction lookup table is a function of engine torque and engine speed where:

- *PM* is the PM emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **PM**.

Engine speed breakpoints, `f_exhfrac_n_bpt` – Breakpoints

```
[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571
2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286
3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000]
(default) | vector
```

Engine speed breakpoints used for the emission mass fractions lookup tables, in rpm.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO₂**, **CO**, **NO_x**, **HC**, or **PM**.

Engine torque breakpoints, `f_exhfrac_trq_bpt` – Breakpoints

```
[0 15 26.4285714285714 37.8571428571429 49.2857142857143 60.7142857142857
72.1428571428571 83.5714285714286 95 106.428571428571 117.857142857143
129.285714285714 140.714285714286 152.142857142857 163.571428571429 175]
(default) | vector
```

Engine torque breakpoints used for the emission mass fractions lookup tables, in N·m.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO₂**, **CO**, **NO_x**, **HC**, or **PM**.

Exhaust gas specific heat at constant pressure, cp_exh — Specific heat
1005 (default) | scalar

Exhaust gas-specific heat, $C_{p_{exh}}$, in J/(kg·K).

Fuel

Stoichiometric air-fuel ratio, afr_stoich — Air-fuel ratio
14.6 (default) | scalar

Air-fuel ratio, AFR .

Fuel lower heating value, fuel_lhv — Heating value
42e6 (default) | scalar

Fuel lower heating value, LHV , in J/kg.

Fuel specific gravity, fuel_sg — Specific gravity
0.832 (default) | scalar

Specific gravity of fuel, $S_{g_{fuel}}$, dimensionless.

Version History

Introduced in R2017a

References

[1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

CI Controller | Mapped CI Engine

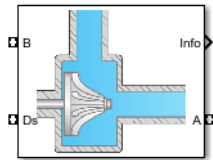
Topics

“CI Core Engine Air Mass Flow and Torque Production”
“Engine Calibration Maps”

Compressor

Compressor for boosted engines

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Boost

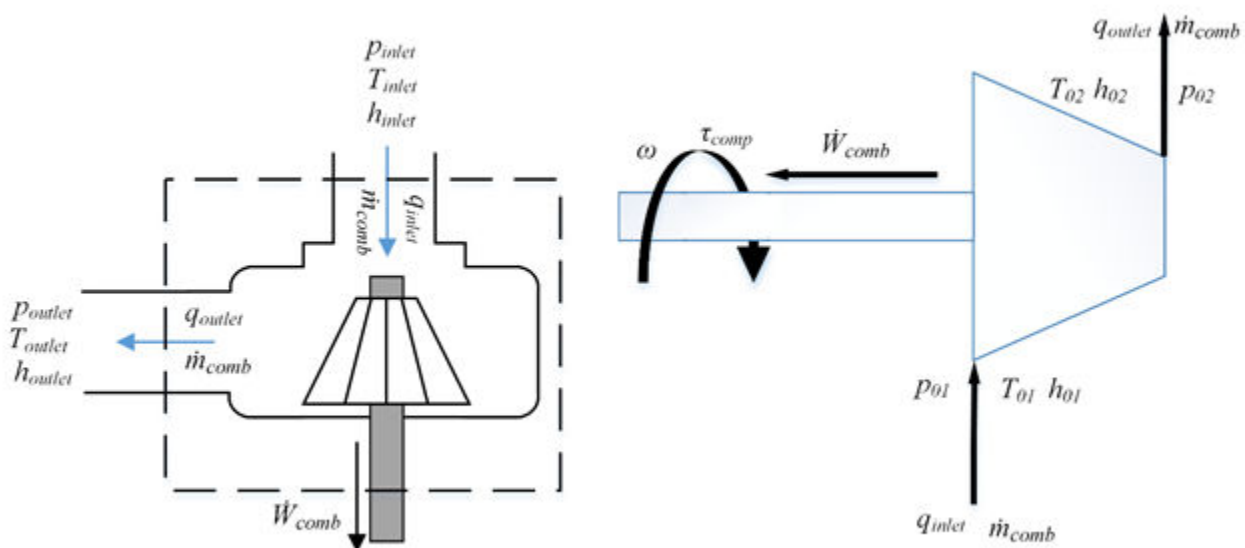


Description

The Compressor block simulates engine boost by using the drive shaft energy to increase the intake manifold pressure. The block is a component of supercharger and turbocharger models. The block uses two-way ports to connect to the inlet and outlet control volumes and the drive shaft. The control volumes provide the pressure, temperature, and specific enthalpy for the compressor to calculate the mass and energy flow rates. To calculate the torque and flow rates, the drive shaft provides the speed to the compressor. Typically, compressor manufacturers provide the mass flow rate and efficiency tables as a function of corrected speed and pressure ratio. You can specify the lookup tables to calculate the mass flow rate and efficiency. The block does not support reverse mass flow.

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the mass flow rate and turbine efficiency lookup tables using measured data.

The mass flows from the inlet control volume to the outlet control volume.



Virtual Calibration

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the mass flow rate and turbine efficiency lookup tables using measured data. The dialog box steps through these tasks.

Task	Description																				
Import compressor data	<p>Import this compressor data from a file. For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <ul style="list-style-type: none"> • Speed, Spd, in rad/s • Mass flow rate, MassFlwRate, in kg/s • Pressure ratio, PrsRatio, dimensionless • Efficiency, Eff, dimensionless <p>The speed, mass flow rate, pressure ratio, and efficiency are in the 2nd-5th columns of the data file, respectively. The first and second rows of the data file provide the variable names and units. For example, use this format.</p> <table border="1"> <tr> <td>Name:</td> <td>Spd</td> <td>MassFlwRate</td> <td>PrsRatio</td> <td>Eff</td> </tr> <tr> <td>Unit:</td> <td>rad/s</td> <td>kg/s</td> <td></td> <td></td> </tr> <tr> <td>Data:</td> <td>8373.3</td> <td>0.02</td> <td>1.21</td> <td>0.44</td> </tr> <tr> <td></td> <td>...</td> <td>...</td> <td>...</td> <td>...</td> </tr> </table> <p>Model-Based Calibration Toolbox limits the speed and pressure ratio breakpoint values to the maximum values in the file.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Name:	Spd	MassFlwRate	PrsRatio	Eff	Unit:	rad/s	kg/s			Data:	8373.3	0.02	1.21	0.44	
Name:	Spd	MassFlwRate	PrsRatio	Eff																	
Unit:	rad/s	kg/s																			
Data:	8373.3	0.02	1.21	0.44																	
																	
Generate response models	<p>Model-Based Calibration Toolbox fits the imported data to the response models.</p> <table border="1"> <thead> <tr> <th>Data</th> <th>Response Model</th> </tr> </thead> <tbody> <tr> <td>Mass flow rate</td> <td>Extended ellipse response model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td>Efficiency</td> <td>Polynomial</td> </tr> </tbody> </table> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>	Data	Response Model	Mass flow rate	Extended ellipse response model described in <i>Modeling and Control of Engines and Drivelines²</i>	Efficiency	Polynomial														
Data	Response Model																				
Mass flow rate	Extended ellipse response model described in <i>Modeling and Control of Engines and Drivelines²</i>																				
Efficiency	Polynomial																				
Generate calibration	<p>Model-Based Calibration Toolbox calibrates the response model and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>																				

Task	Description
Update block parameters	Update these mass flow rate and efficiency parameters with the calibration. <ul style="list-style-type: none"> • Corrected mass flow rate table, \dot{m}_{corr_tbl} • Efficiency table, η_{comp_tbl} • Corrected speed breakpoints, w_corr_bpts1 • Pressure ratio breakpoints, Pr_bpts2

Thermodynamics

The block uses these equations to model the thermodynamics.

Calculation	Equations
Forward mass flow	$\dot{m}_{comp} > 0$ $p_{01} = p_{inlet}$ $p_{02} = p_{outlet}$ $T_{01} = T_{inlet}$ $h_{01} = h_{inlet}$
First law of thermodynamics	$\dot{W}_{comp} = \dot{m}_{comp} c_p (T_{01} - T_{02})$
Isentropic efficiency	$\eta_{comp} = \frac{h_{02s} - h_{01}}{h_{02} - h_{01}} = \frac{T_{02s} - T_{01}}{T_{02} - T_{01}}$
Isentropic outlet temperature, assuming ideal gas and constant specific heats	$T_{02s} = T_{01} \left(\frac{p_{02}}{p_{01}} \right)^{\frac{\gamma - 1}{\gamma}}$
Specific heat ratio	$\gamma = \frac{c_p}{c_p - R}$
Outlet temperature	$T_{02} = T_{01} + \frac{T_{01}}{\eta_{comb}} \left\{ \left(\frac{p_{02}}{p_{01}} \right)^{\frac{\gamma - 1}{\gamma}} - 1 \right\}$
Heat flows	$q_{inlet} = \dot{m}_{comp} h_{01}$ $q_{outlet} = \dot{m}_{comp} h_{02} = \dot{m}_{comp} c_p T_{02}$
Corrected mass flow rate	$\dot{m}_{corr} = \dot{m}_{comp} \frac{\sqrt{T_{01}/T_{ref}}}{p_{01}/p_{ref}}$
Corrected speed	$\omega_{corr} = \frac{\omega}{\sqrt{T_{01}/T_{ref}}}$
Pressure ratio	$p_r = \frac{p_{01}}{p_{02}}$

The block uses the internal signal `FlwDir` to track the direction of the flow.

The equations use these variables.

p_{inlet}, p_{01}	Inlet control volume total pressure
T_{inlet}, T_{01}	Inlet control volume total temperature
h_{inlet}, h_{01}	Inlet control volume total specific enthalpy
p_{outlet}, p_{02}	Outlet control volume total pressure
T_{outlet}	Outlet control volume total temperature
h_{outlet}	Outlet control volume total specific enthalpy
\dot{W}_{comp}	Drive shaft power
T_{02}	Outlet total temperature
h_{02}	Outlet total specific enthalpy
\dot{m}_{comp}	Mass flow rate through compressor
q_{inlet}	Inlet heat flow rate
q_{outlet}	Outlet heat flow rate
η_{comp}	Compressor isentropic efficiency
T_{02s}	Isentropic outlet total temperature
h_{02s}	Isentropic outlet total specific enthalpy
R	Ideal gas constant
c_p	Specific heat at constant pressure
γ	Specific heat ratio
\dot{m}_{corr}	Corrected mass flow rate
ω	Drive shaft speed
ω_{corr}	Corrected drive shaft speed
T_{ref}	Lookup table reference temperature
P_{ref}	Lookup table reference pressure
τ_{comp}	Compressor drive shaft torque
p_r	Pressure ratio
$\eta_{comb, tbl}$	Compressor efficiency 3-D lookup table
$\dot{m}_{corr, tbl}$	Corrected mass flow rate 3-D lookup table
$\omega_{corr, bpts1}$	Corrected speed breakpoints
$p_r, bpts2$	Pressure ratio breakpoints

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrDriveshaft	Power transmitted from the shaft
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrHeatFlwIn	Heat flow rate at port A
		PwrHeatFlwOut	Heat flow rate at port B
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrLoss	Power loss
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 		
PwrStored — Stored energy rate of change	<i>Not used</i>		
<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 			

The equations use these variables.

\dot{W}_{turb}	Drive shaft power
q_{outlet}	Total outlet heat flow rate
q_{inlet}	Total inlet heat flow rate

Ports

Input

Ds — Drive shaft speed

two-way connector port

ShftSpd — Signal containing the drive shaft angular speed, ω , in rad/s.

A — Inlet pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the inlet control volume:

- InPrs — Pressure, p_{inlet} , in Pa
- InTemp — Temperature, T_{inlet} , in K
- InEnth — Specific enthalpy, h_{inlet} , in J/kg

B — Outlet pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the outlet control volume:

- OutPrs — Pressure, p_{outlet} , in Pa
- OutTemp — Temperature, T_{outlet} , in K
- OutEnth — Specific enthalpy, h_{outlet} , in J/kg

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
CmprsOutletTemp		Temperature exiting the compressor	K	
DriveshftPwr		Drive shaft power	W	
DriveshftTrq		Drive shaft torque	N·m	
CmprsMassFlw		Mass flow rate through compressor	kg/s	
PrsRatio		Pressure ratio	N/A	
DriveshftCorrSpd		Corrected drive shaft speed	rad/s	
CmprsEff		Compressor isentropic efficiency	N/A	
CorrMassFlw		Corrected mass flow rate	kg/s	
PwrInfo	PwrTrnsfrd	PwrDriveshft	Power transmitted from the shaft	W
		PwrHeatFlwIn	Heat flow rate at port A	W
		PwrHeatFlwOut	Heat flow rate at port B	W
	PwrNotTrnsfrd	PwrLoss	Power loss	W
	PwrStored		<i>Not used</i>	W

Ds — Drive shaft torque

two-way connector port

Trq — Signal containing the drive shaft torque, τ_{comp} , in N·m.

A — Inlet mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing:

- MassFlwRate — Mass flow rate through inlet, \dot{m}_{comp} , in kg/s
- HeatFlwRate — Inlet heat flow rate, q_{inlet} , in J/s
- Temp — Inlet temperature, in K
- MassFrac — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

B — Outlet mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing:

- MassFlwRate — Outlet mass flow rate, \dot{m}_{comp} , in kg/s
- HeatFlwRate — Outlet heat flow rate, q_{outlet} , in J/s
- Temp — Outlet temperature, in K
- MassFrac — Outlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
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- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Parameters

Performance Tables

Calibrate Performance Maps — Calibrate tables with measured data selection

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the mass flow rate and turbine efficiency lookup tables using measured data. The dialog box steps through these tasks.

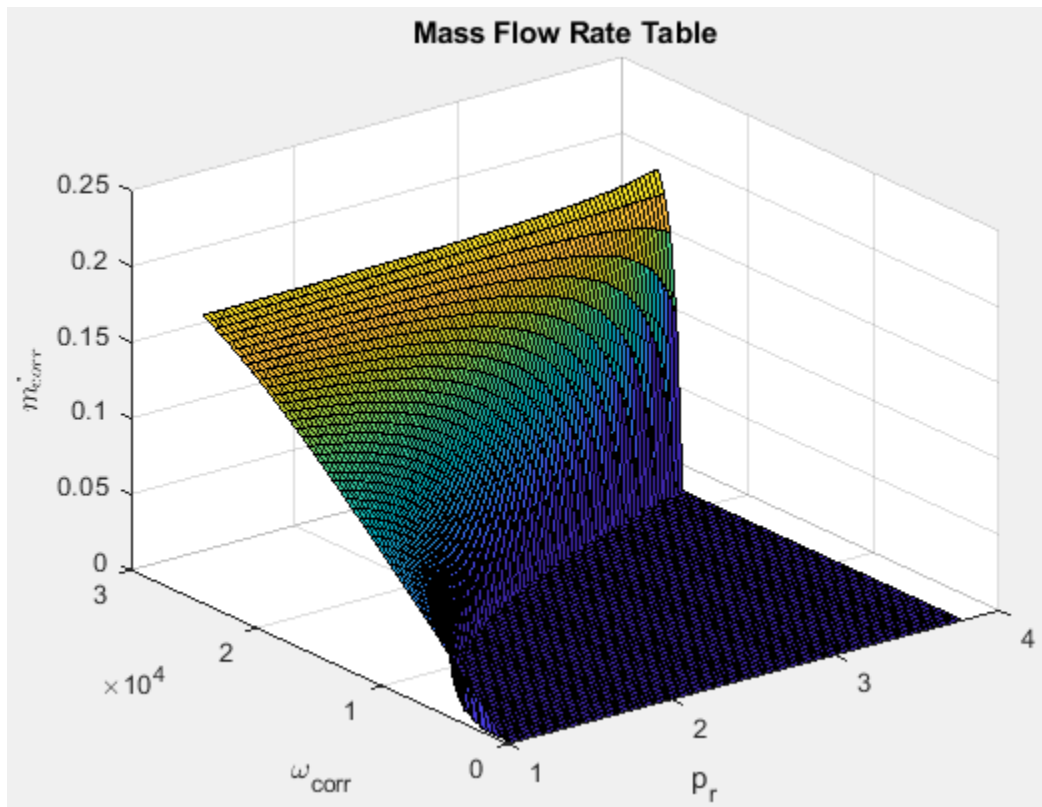
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Task	Description
Update block parameters	Update these mass flow rate and efficiency parameters with the calibration. <ul style="list-style-type: none"> • Corrected mass flow rate table, \dot{m}_{corr_tbl} • Efficiency table, η_{comp_tbl} • Corrected speed breakpoints, ω_{corr_bpts1} • Pressure ratio breakpoints, Pr_bpts2

Corrected mass flow rate table, \dot{m}_{corr_tbl} – Lookup table

array

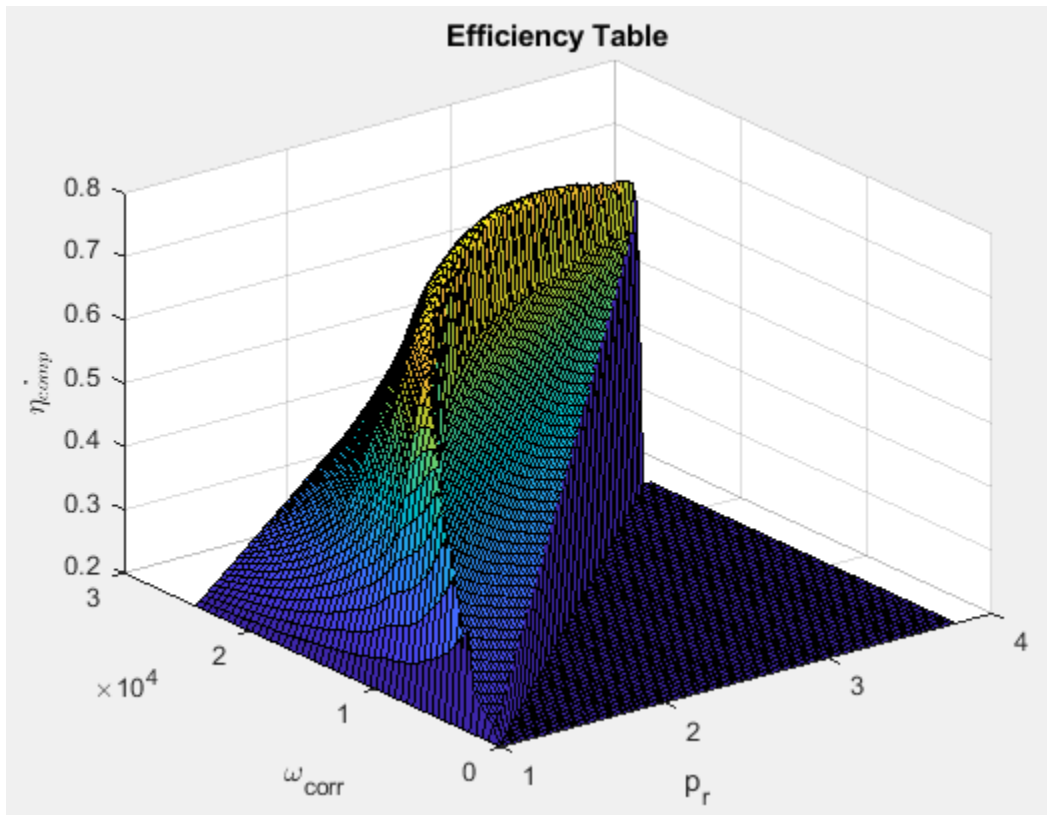
Corrected mass flow rate lookup table, \dot{m}_{corr_tbl} , as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , in kg/s.



Efficiency table, η_{comp_tbl} – Lookup table

array

Efficiency lookup table, η_{comb_tbl} , as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , dimensionless.



Corrected speed breakpoints, w_corr_bpts1 – Breakpoints
vector

Corrected drive shaft speed breakpoints, $\omega_{corr, bpts1}$, in rad/s.

Pressure ratio breakpoints, Pr_bpts2 – Breakpoints
vector

Pressure ratio breakpoints, $p_{r, bpts2}$.

Reference temperature, T_ref – Reference
293.15 (default) | scalar

Lookup table reference temperature, T_{ref} , in K.

Reference pressure, P_ref – Reference
101325 (default) | scalar

Lookup table reference pressure, P_{ref} , in Pa.

Gas Properties

Ideal gas constant, R – Constant
287 (default) | scalar

Ideal gas constant, R , in J/(kg*K).

Specific heat at constant pressure, cp — Specific heat
1005 (default) | scalar

Specific heat at constant pressure, c_p , in J/(kg*K).

Version History

Introduced in R2017a

References

- [1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.
- [2] Eriksson, Lars and Lars Nielsen. *Modeling and Control of Engines and Drivelines*. Chichester, West Sussex, United Kingdom: John Wiley & Sons Ltd, 2014.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Boost Drive Shaft | Turbine

Topics

“Model-Based Calibration Toolbox”

Control Volume System

Constant volume open thermodynamic system with heat transfer

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Fundamental Flow



Description

The Control Volume System block models a constant volume open thermodynamic system with heat transfer. The block uses the conservation of mass and energy, assuming an ideal gas, to determine the pressure and temperature. The block implements an automotive-specific Constant Volume Pneumatic Chamber block that includes thermal effects related to the under hood of passenger vehicles. You can specify heat transfer models:

- Constant
- External input
- External wall convection

You can use the Control Volume System block to represent engine components that contain volume, including pipes and manifolds.

Thermodynamics

The Control Volume System block implements a constant volume chamber containing an ideal gas. To determine the rate changes in temperature and pressure, the block uses the continuity equation and the first law of thermodynamics.

$$\frac{dT_{vol}}{dt} = \frac{RT_{vol}}{c_v V_{ch} P_{vol}} \left(\sum (q_i - T_{vol} c_v \dot{m}_i) - Q_{wall} \right)$$

$$\frac{dP_{vol}}{dt} = \frac{P_{vol}}{T_{vol}} \frac{dT_{vol}}{dt} + \frac{RT_{vol}}{V_{ch}} \sum \dot{m}_i$$

The block uses this equation for the volume-specific enthalpy.

$$h_{vol} = c_p T_{vol}$$

The equations use these variables.

\dot{m}_i	Mass flow rate at port
q_i	Heat flow rate at port
V_{ch}	Chamber volume
P_{vol}	Absolute pressure in the chamber
R	Ideal gas constant
c_v	Specific heat at constant volume

T_{vol}	Absolute gas temperature
Q_{wall}	Wall heat transfer rate
h_{vol}	Volume-specific enthalpy
c_p	Specific heat capacity

Mass Fractions

The Control Volume Source block is part of a flow network. Blocks in the network determine the mass fractions that the block will track during simulation. The block can track these mass fractions:

- O₂ — Oxygen
- N₂ — Nitrogen
- UnburnedFuel — Unburned fuel
- CO₂ — Carbon dioxide
- H₂O — Water
- CO — Carbon monoxide
- NO — Nitric oxide
- NO₂ — Nitrogen dioxide
- PM — Particulate matter
- Air — Air
- BurnedGas — Burned gas

Using the conservation of mass for each gas constituent, this equation determines the rate change:

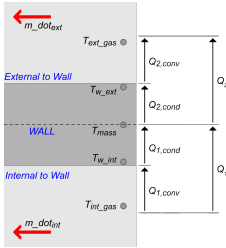
$$\frac{dy_{vol,j}}{dt} = \frac{RT_{vol}}{P_{vol}V_{ch}} (\sum \dot{m}_i y_{i,j} + y_{vol,j} \sum \dot{m}_i)$$

The equations use these variables.

V_{ch}	Chamber volume
P_{vol}	Absolute pressure in the chamber
R	Ideal gas constant
T_{vol}	Absolute gas temperature
$y_{i,j}$	I-th port mass fraction for $j = \text{O}_2, \text{N}_2, \text{unburned fuel}, \text{CO}_2, \text{H}_2\text{O}, \text{CO}, \text{NO}, \text{NO}_2, \text{PM}, \text{air}, \text{and burned gas}$
$y_{vol,j}$	Control volume mass fraction for $j = \text{O}_2, \text{N}_2, \text{unburned fuel}, \text{CO}_2, \text{H}_2\text{O}, \text{CO}, \text{NO}, \text{NO}_2, \text{PM}, \text{air}, \text{and burned gas}$
\dot{m}_i	Mass flow rate for $i = \text{O}_2, \text{N}_2, \text{unburned fuel}, \text{CO}_2, \text{H}_2\text{O}, \text{CO}, \text{NO}, \text{NO}_2, \text{PM}, \text{air}, \text{and burned gas}$

External Wall Convection Heat Transfer Model

To calculate the heat transfer, you can configure the Control Volume Source block to calculate the heat transfer across the wall of the control volume.



The block implements these equations to calculate the heat transfer, Q_1 , from the internal control volume gas to the internal wall depth, D_{int_cond} .

$$Q_1 = Q_{1,conv} = Q_{1,cond}$$

$$Q_{1,conv} = h_{int}(x_{int}) \cdot A_{int_conv} \cdot (T_{int_gas} - T_{w_int})$$

$$Q_{1,cond} = k_{int} \cdot \frac{A_{int_cond}}{D_{int_cond}} \cdot (T_{w_int} - T_{mass})$$

The block implements these equations to calculate the heat transfer, Q_2 , from the external wall depth, D_{ext_cond} to the external gas.

$$Q_2 = Q_{2,conv} = h_{ext}(x_{ext}) \cdot A_{ext_conv} \cdot (T_{w_ext} - T_{ext_gas})$$

$$Q_{2,cond} = k_{ext} \cdot \frac{A_{ext_cond}}{D_{ext_cond}} \cdot (T_{mass} - T_{w_ext})$$

This equation expresses the heat stored in the thermal mass.

$$\frac{dT_{mass}}{dt} = \frac{Q_1 - Q_2}{c_{pwall} m_{wall}}$$

The block determines the interior convection heat transfer coefficient using a lookup table that is a function of the average mass flow rate.

$$\dot{m}_{int_gas} = \frac{1}{2} \sum |\dot{m}_i|$$

The equations use these variables.

Q_1	Heat flow from the internal gas to a specified wall depth
$Q_{1,conv}$	Heat flow convection from the internal gas to the internal wall
$Q_{1,cond}$	Conduction heat transfer rate
Q_2	Heat transfer rate
$Q_{2,conv}$	Convection heat transfer
$Q_{2,cond}$	Heat flow conduction from the external middle portion of the wall to the external wall
Q_{mass}	Heat stored in thermal mass
h_{int}	Internal convection heat transfer coefficient
x_{int}	Internal mass flow rate breakpoints

A_{int_conv}	Internal flow convection area
T_{int_gas}	Temperature of the gas inside the chamber
T_{w_int}	Temperature of the inside wall of the chamber
k_{int}	Internal wall thermal conductivity
A_{int_cond}	Internal conduction area
D_{int_cond}	Internal wall thickness
h_{ext}	External convection heat transfer coefficient
x_{ext}	External velocity breakpoints
A_{ext_conv}	External convection area
T_{ext_gas}	External gas temperature
T_{w_ext}	Temperature of the external wall of the chamber
k_{ext}	External wall thermal conductivity
A_{ext_cond}	External conduction area
D_{ext_cond}	External wall thickness
T_{mass}	Temperature of the thermal mass
c_{p_wall}	Wall heat capacity
m_{wall}	Thermal mass
Flw_{spd}	External flow velocity
\dot{m}_{int_gas}	Average internal mass flow rate

Power Accounting

For the power accounting, the block implements these equation based on the number of inlet and outlet ports.

Bus Signal		Description	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrHeatFl wi	Port i heat flow q_i
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrHeatTr nsfr	Heat transfer rate from wall to control volume $-Q_{wall}$

Bus Signal		Description	Equations
PwrStored	— Stored energy rate of change • Positive signals indicate an increase • Negative signals indicate a decrease	PwrHeatStored	Rate of heat stored in the control volume $\left(\sum (q_i) - Q_{wall} \right)$

For example, if you configure your block with 3 input ports and 2 outlet ports, the block implements these equations

Bus Signal		Description	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrHeatFlw1	Inlet port 1 heat flow q_1
		PwrHeatFlw2	Inlet port 2 heat flow q_2
		PwrHeatFlw3	Inlet port 3 heat flow q_3
		PwrHeatFlw4	Outlet port 4 heat flow q_4
		PwrHeatFlw5	Outlet port 5 heat flow q_5
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrHeatTrnsfr	Heat transfer rate from wall to control volume $-Q_{wall}$
PwrStored	— Stored energy rate of change • Positive signals indicate an increase • Negative signals indicate a decrease	PwrHeatStored	Rate of heat stored in the control volume $\left(\sum (q_i) - Q_{wall} \right)$

Ports

Input

C — Inlet mass flow rate, heat flow rate, mass fractions

two-way connector port

Bus containing:

- MassFlw — Mass flow rate through inlet, in kg/s
- HeatFlw — Inlet heat flow rate, in J/s

- **MassFrac** — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- **O2MassFrac** — Oxygen
- **N2MassFrac** — Nitrogen
- **UnbrndFuelMassFrac** — Unburned fuel
- **C02MassFrac** — Carbon dioxide
- **H20MassFrac** — Water
- **C0MassFrac** — Carbon monoxide
- **N0MassFrac** — Nitric oxide
- **N02MassFrac** — Nitrogen dioxide
- **N0xMassFrac** — Nitric oxide and nitrogen dioxide
- **PmMassFrac** — Particulate matter
- **AirMassFrac** — Air
- **BrndGasMassFrac** — Burned gas

Dependencies

To create input ports, specify the **Number of inlet ports** parameter.

HeatTrnsfrRate — Heat transfer

scalar

External heat transfer input to control volume, q_{he} , in Kg/s.

Dependencies

To create this port, select External input for the **Heat transfer model** parameter.

ExtnlFlwVel — External flow velocity

scalar

External flow velocity, Flw_{spd} , in m/s.

Dependencies

To create this port, select External wall convection for the **Heat transfer model** parameter.

ExtnlTemp — Ambient temperature, K

scalar

Dependencies

To create this port, select External wall convection for the **Heat transfer model** parameter.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units	
Vol	Prs	Volume pressure	Pa	
	Temp	Volume temperature	K	
	Enth	Volume specific enthalpy	J/kg	
	Species	O2MassFrac	Oxygen mass fraction	NA
		N2MassFrac	Nitrogen mass fraction	NA
		UnbrndFuelMassFrac	Unburned gas mass fraction	NA
		CO2MassFrac	Carbon dioxide mass fraction	NA
		H2OMassFrac	Water mass fraction	NA
		COMassFrac	Carbon monoxide mass fraction	NA
		NOMassFrac	Nitric oxide mass fraction	NA
		NO2MassFrac	Nitrogen dioxide mass fraction	NA
		NOxMassFrac	Nitric oxide and nitrogen dioxide mass fraction	NA
		PmMassFrac	Particulate matter mass fraction	NA
AirMassFrac	Air mass fraction	NA		
BrndGasMassFrac	Burned gas mass fraction	NA		
HeatTrnsfr	HeatTrnsfrRate		Wall heat transfer rate	J/s
	MassFlw		Average internal mass flow rate	kg/s
	IntrnTemp		Temperature of gas inside chamber	K
PwrInfo	PwrTrnsfrd	PwrHeatFlwi	Port <i>i</i> heat flow	W
	PwrNotTrnsfrd	PwrHeatTrnsfr	Heat transfer rate from wall to control volume	W
	PwrStored	PwrHeatStored	Rate of heat stored in the control volume	W

C – Outlet pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the outlet control volume:

- Prs — Chamber pressure, in Pa
- Temp — Gas temperature, in K

- Enth — Specific enthalpy, in J/kg
- MassFrac — Mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Dependencies

To create outlet ports, specify the **Number of outlet ports** parameter.

Parameters

Block Options

Number of inlet ports — Number of ports

1 (default) | 0 | 2 | 3 | 4

Number of inlet ports.

Dependencies

To create inlet ports, specify the number.

Number of outlet ports — Number of ports

1 (default) | 0 | 2 | 3 | 4

Number of outlet ports.

Dependencies

To create outlet ports, specify the number.

Heat transfer model — Select model

Constant (default) | External input | External wall convection

Dependencies

Selecting Constant or External wall convection enables the **Heat Transfer** parameters.

Image type — Icon color

Cold (default) | Hot

Select color for block icon:

- Cold for blue
- Hot for red

General**Chamber volume, Vch — Volume**

0.0029 (default) | scalar

Chamber volume, V_{ch} , in m^3 .**Initial chamber pressure, Pinit — Pressure**

101325 (default) | scalar

Initial chamber pressure, P_{vol} , in Pa.**Initial chamber temperature, Tinit — Temperature**

298 (default) | scalar

Initial chamber temperature, T_{vol} , in K.**Ideal gas constant, R — Ideal gas constant**

287 (default) | scalar

Ideal gas constant, R , in $J/(kg \cdot K)$.**Specific heat capacity, cp — Specific heat**

1005 (default) | scalar

Specific heat capacity, c_p , in $J/(kg \cdot K)$.**Heat Transfer****Heat transfer rate, q_he — Rate**

0 (default) | scalar

Constant heat transfer rate, q_{he} , in J/s.**Dependencies**To enable this parameter, select Constant for the **Heat transfer model** parameter.**External convection heat transfer coefficient, ext_tbl — Manifold external air**

[40 160 740 2000] (default) | vector

External convection heat transfer coefficient, h_{ext} , in $W/(m^2K)$.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

External velocity breakpoints, ext_bpts – Manifold external air

linspace(0,180,4) (default) | vector

External velocity breakpoints, x_{ext} , in m/s.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**External convection area, Aext_conv – Manifold external air**

0.125 (default) | scalar

External convection area, A_{ext_conv} , in m^2 .**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**Thermal mass, m_wall – Manifold wall general**

7 (default) | scalar

Thermal mass, m_{wall} , in kg.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**Wall heat capacity, cp_wall – Manifold wall general**

900 (default) | scalar

Wall heat capacity, c_{p_wall} , in $J/(kg \cdot K)$.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**Initial mass temperature, Tmass – Manifold wall general**

293.15 (default) | scalar

Initial mass temperature, T_{mass} , in K.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**External wall thickness, Dext_cond – Manifold wall external**

0.004 (default) | scalar

External wall thickness, D_{ext_cond} , in m.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

External conduction area, Aext_cond – Manifold wall external

0.003 (default) | scalar

External conduction area, A_{ext_cond} , in m^2 .**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

External wall thermal conductivity, kint – Manifold wall external

25 (default) | scalar

External wall thermal conductivity, k_{ext} , in $W/(m \cdot K)$.**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Internal wall thickness, Dint_cond – Manifold wall internal

0.004 (default) | scalar

Internal wall thickness, D_{int_cond} , in m.**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Internal conduction area, Aint_cond – Manifold wall internal

0.003 (default) | scalar

Internal conduction area, A_{int_cond} , in m^2 .**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Internal wall thermal conductivity, kint – Manifold wall internal

25 (default) | scalar

Internal wall thermal conductivity, k_{int} , in $W/(m \cdot K)$.**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Internal convection heat transfer coefficient, int_tbl – Manifold internal air

[40 160 740 2000] (default) | vector

Internal convection heat transfer coefficient, h_{int} , in $W/(m^2K)$.**Dependencies**

To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Internal mass flow rate breakpoints, `int_bpts` – Manifold internal air`linspace(0.0020,0.1100,4)` (default) | vectorInternal velocity breakpoints, x_{int} , in kg/s.**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.**Internal flow convection area, `Aint_conv` – Manifold internal air**`0.125` (default) | scalarInternal convection area, A_{int_conv} , in m².**Dependencies**To enable this parameter, select External wall convection for the **Heat transfer model** parameter.

Version History

Introduced in R2017a

References

[1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Flow Restriction | Heat Exchanger | Constant Volume Pneumatic Chamber (Simscape)

Flow Boundary

Flow boundary for ambient temperature and pressure

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Fundamental Flow



Description

The Flow Boundary block implements a flow boundary that typically represents ambient temperature and pressure. Engine models require flow boundaries at the intake inlet and exhaust outlet. In dynamic engine models, flow-modifying components (for example, flow restriction, turbines, and compressors) connect to control volumes and flow boundaries.

You can specify these block configurations:

- Constant pressure and temperature
- Externally input pressure and temperature

The Flow Boundary block outputs pressure, temperature, and specific enthalpy:

$$h = c_p T$$

The block models the mass fractions as dry air, resulting in these mass fractions:

- $y_{N_2} = 0.767$
- $y_{O_2} = .233$

The equation uses these variables.

T	Temperature
h	Specific enthalpy
c_p	Specific heat at constant pressure
y_{N_2}	Nitrogen mass fraction
y_{O_2}	Oxygen mass fraction

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBndrFlw	Heat flow rate to flow restriction q_{orf}
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrEnv	Heat flow rate to environment $-q_{orf}$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	<i>Not used</i>	

Ports

Input

Prs — Pressure

scalar

External input pressure, P , in Pa.

Dependencies

To create this port, select External input for the **Pressure and temperature source** parameter.

Temp — Temperature

scalar

External input temperature, T , in K.

Dependencies

To create this port, select External input for the **Pressure and temperature source** parameter.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units
BndryPrs		Boundary pressure	Pa
BndryTemp		Boundary temperature	K
BndryEnth		Boundary specific enthalpy	J/kg
PwrInfo	PwrTrnsfrd	PwrBndryFlw	Heat flow rate to flow restriction
	PwrNotTrnsfrd	PwrEnv	Heat flow rate to environment
	PwrStored		<i>Not used</i>

C – Boundary pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the flow boundary:

- Prs — Pressure, P , in Pa
- Temp — Temperature, T , in K
- Enth — Specific enthalpy, h , in J/kg
- MassFrac — Mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Parameters

Block Options

Pressure and temperature source – Select source

External input (default) | Constant

Pressure and temperature source.

Dependencies

The table summarizes the parameter and port dependencies.

Value	Enables Parameters	Creates Ports
Constant	Pressure, Pcnst Temperature, Tcnst	None
External input	None	Prs Temp

Image type — Icon color

Cold (default) | Hot

Select color for block icon:

- Cold for blue
- Hot for red

Pressure, Pcnst — Constant

101325 (default) | scalar

Constant pressure, P , in Pa.

Dependencies

To enable this parameter, select Constant for the **Pressure and temperature source** parameter.

Temperature, Tcnst — Constant

298.15 (default) | scalar

Constant temperature, T , in K.

Dependencies

To enable this parameter, select Constant for the **Pressure and temperature source** parameter.

Specific heat at constant pressure, cp — Constant

1005 (default) | scalar

Specific heat at constant pressure, in J/(kg·K).

Version History

Introduced in R2017a

References

[1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

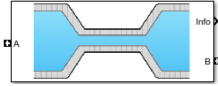
See Also

Compressor | Flow Restriction | Turbine

Flow Restriction

Isentropic ideal gas flow through an orifice

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Fundamental Flow



Description

The Flow Restriction block models isentropic ideal gas flow through an orifice. The block uses the conservation of mass and energy to determine the mass flow rate. The flow velocity is limited by choked flow.

You can specify these orifice area models:

- Constant
- External input
- Throttle body geometry

Equations

The Flow Restriction block implements these equations.

Calculation	Equations
Standard orifice	$\dot{m}_{orf} = \Gamma \cdot \Psi(P_{ratio})$ $P_{ratio} = \frac{P_{downstr}}{P_{upstr}}$ $\Gamma = \frac{A_{eff} \cdot P_{upstr}}{\sqrt{R \cdot T_{upstr}}}$ $P_{cr} = \left(\frac{2}{\gamma + 1}\right)^{\frac{\gamma}{\gamma - 1}}$ $\Psi = \begin{cases} \sqrt{\gamma \left(\frac{2}{\gamma + 1}\right)^{\frac{\gamma + 1}{\gamma - 1}}} & P_{ratio} < P_{cr} \\ \sqrt{\frac{2\gamma}{\gamma - 1} \left(P_{ratio}^{\frac{2}{\gamma}} - P_{ratio}^{\frac{\gamma + 1}{\gamma}}\right)} & P_{cr} \leq P_{ratio} \leq P_{lim} \\ \frac{P_{ratio} - 1}{P_{lim} - 1} \sqrt{\frac{2\gamma}{\gamma - 1} \left(P_{lim}^{\frac{2}{\gamma}} - P_{lim}^{\frac{\gamma + 1}{\gamma}}\right)} & P_{lim} < P_{ratio} \end{cases}$
Constituent mass flow rates	$\dot{m}_i = \dot{m}_{orf} y_{upstr, i}$
Constant orifice area	$A_{eff} = A_{orf_cnst} \cdot C_{d_{cnst}}$

Calculation	Equations
External input orifice area	$A_{eff} = A_{orf_ext} \cdot Cd_{ext}$
Throttle body geometry	$\theta_{thr} = Pct_{thr} \cdot \frac{90}{100}$ $A_{eff_thr} = \frac{\pi}{4} D_{thr}^2 C_{d_thr}(\theta_{thr})$
Heat flow rate	$q_{orf} = \dot{m}_{orf} h_{upstr}$

The equations use these variables.

A_{eff}, A_{eff_thr}	Effective orifice cross-sectional area
$A_{orf_cnst}, A_{orf_ext}$	Orifice area
Cd_{cnst}, Cd_{ext}	Discharge coefficient
R	Ideal gas constant
P_{cr}	Critical pressure at which choked flow occurs
γ	Ratio of specific heats
Γ	Flow function based on pressure ratio
P_{ratio}	Pressure ratio
P_{upstr}	Upstream orifice pressure
$P_{downstr}$	Downstream orifice pressure
P_{lim}	Pressure ratio limit to avoid singularities as the pressure ratio approaches 1
$y_{upstr,i}$	Upstream species mass fraction for $i = O_2, N_2, \text{unburned fuel}, CO_2, H_2O, CO, NO, NO_2, PM, \text{air}, \text{and burned gas}$
\dot{m}_i	Mass flow rate for $i = O_2, N_2, \text{unburned fuel}, CO_2, H_2O, CO, NO, NO_2, PM, \text{air}, \text{and burned gas}$
θ_{thr}	Throttle angle
Pct_{thr}	Percentage of throttle body that is open
C_{d_thr}	Throttle discharge coefficient
D_{thr}	Throttle body diameter at opening
\dot{m}_{orf}	Orifice mass flow
h_{upstr}	Upstream specific enthalpy
q_{orf}	Heat flow rate

The block uses the internal signal `FlwDir` to track the direction of the flow.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Descripti on	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrHeatFlwIn	Heat flow rate at port A q_{orf}
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrHeatFlwOut	Heat flow rate at port B $-q_{orf}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	<i>Not used</i>	
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 		
PwrStored	PwrStored — Stored energy rate of change	<i>Not used</i>	
	<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 		

Ports

Input

A — Inlet orifice pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing orifice:

- Prs — Pressure, in Pa
- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

B — Outlet orifice pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing orifice:

- Prs — Pressure, in Pa
- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Outlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Area — Orifice area

scalar

External area input for orifice area, A_{orf_ext} , in m^2 .**Dependencies**To create this port, select External input for the **Orifice area model** parameter.**ThrPct — Throttle body percent open**

scalar

Percentage of throttle body that is open, Pct_{thr} .**Dependencies**To create this port, select Throttle body geometry for the **Orifice area model** parameter.**Output****A — Inlet mass flow rate, heat flow rate, temperature**

two-way connector port

Bus containing:

- MassFlw — Mass flow rate through inlet, in kg/s
- HeatFlw — Inlet heat flow rate, in J/s
- Temp — Inlet temperature, in K
- MassFrac — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

B — Outlet mass flow rate, heat flow rate, temperature
two-way connector port

Bus containing:

- MassFlw — Outlet mass flow rate, in kg/s
- HeatFlw — Outlet heat flow rate, in J/s
- Temp — Outlet temperature, in K
- MassFrac — Outlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Units		
Flw	PrsAdj	DwnstrmPrs	Downstream pressure	Pa	
		UpstrmPrs	Upstream pressure	Pa	
		PrsRatio	Pressure ratio	NA	
		DwnstrmTemp	Downstream temperature	K	
		UpstrmTemp	Upstream temperature	K	
	OrfMassFlw		Mass flow rate through orifice	kg/s	
	Species	O2MassFlw	Oxygen mass flow rate	kg/s	
		N2MassFlw	Nitrogen mass flow rate	kg/s	
		UnbrndFuelMassFlw	Unburned gas mass flow rate	kg/s	
		CO2MassFlw	Carbon dioxide mass flow rate	kg/s	
		H2OMassFlw	Water mass flow rate	kg/s	
		COMassFlw	Carbon monoxide mass flow rate	kg/s	
		NOMassFlw	Nitric oxide mass flow rate	kg/s	
		NO2MassFlw	Nitrogen dioxide mass flow rate	kg/s	
		NOxMassFlw	Nitric oxide and nitrogen dioxide mass flow rate	kg/s	
		PmMassFlw	Particulate matter mass flow rate	kg/s	
		AirMassFlw	Air mass flow rate	kg/s	
		BrnedGasMassFlw	Burned gas mass flow rate	kg/s	
	PwrInfo	PwrTrnsfrd	PwrHeatFlwIn	Heat flow rate at port A	W
			PwrHeatFlwOut	Heat flow rate at port B	W
PwrNotTrnsfrd		<i>Not used</i>			
PwrStored		<i>Not used</i>			
Area	FlwArea		Cross-sectional flow area	m ²	
	EffctArea		Effective orifice cross-sectional area	m ²	
	ThrAng		Throttle area, if applicable	deg	

Parameters

Block Options

Orifice area model — Select model

Constant (default) | External input | Throttle body geometry

Orifice area model.

Dependencies

The orifice area model enables the parameters on the **Area Parameters** tab.

Image type — Icon color

Cold (default) | Hot

Block icon color:

- Cold for blue.
- Hot for red.

General

Ratio of specific heats, gamma — Ratio

1.3998 (default) | scalar

Ratio of specific heats, γ .

Ideal gas constant, R — Constant

287.05 (default) | scalar

Ideal gas constant, R , in J/(kg·K).

Pressure ratio linearize limit, P_{lim} — Limit

0.95 (default) | scalar

Pressure ratio limit to avoid singularities as the pressure ratio approaches 1, P_{lim} .

Area

Constant area value, A_{orf_cnst} — Area

.1 (default) | scalar

Constant area value, A_{orf_cnst} , in m^2 .

Dependencies

To enable this parameter, select Constant for the **Orifice area model** parameter.

Discharge coefficient, Cd_cnst — Coefficient

1 (default) | scalar

Discharge coefficient for constant area, Cd_{cnst} .

Dependencies

To enable this parameter, select Constant for the **Orifice area model** parameter.

Discharge coefficient, Cd_ext – Coefficient

1 (default) | scalar

Discharge coefficient for external area input, Cd_{ext} .**Dependencies**To enable this parameter, select External input for the **Orifice area model** parameter.**Throttle diameter, Dthr – Diameter**

50 (default) | scalar

Throttle body diameter at opening, D_{thr} , in mm.**Dependencies**To enable this parameter, select Throttle body geometry for the **Orifice area model** parameter.**Discharge coefficient table, ThrCd – Coefficient**

[0.001; 0.735] (default) | vector

Discharge coefficient table, Cd_{thr} .**Dependencies**To enable this parameter, select Throttle body geometry for the **Orifice area model** parameter.**Angle breakpoints, ThrAngBpts – Angle**

[0; 90] (default) | vector

Angle breakpoints, Thr_{ang_bpts} , in deg.**Dependencies**To enable this parameter, select Throttle body geometry for the **Orifice area model** parameter.

Version History

Introduced in R2017a

References

[1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

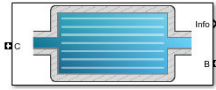
See Also

Control Volume System | Heat Exchanger

Heat Exchanger

Intercooler or exhaust gas recirculation (EGR) cooler

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Fundamental Flow



Description

The Heat Exchanger block models a heat exchanger, for example, an intercooler or exhaust gas recirculation (EGR) cooler. The inlet (port C) connects to an engine flow component (flow restriction, compressor, turbine, or engine block). The outlet (port B) connects to a volume (control volume or environment). Based on the upstream temperature, heat exchanger effectiveness, and cooling medium temperature, the block determines the heat transfer rate and downstream temperature.

For the heat exchanger effectiveness and cooling medium temperature, you can specify either a constant value or an external input. For example, if you specify a heat exchanger effectiveness that is:

- Equal to 1, the downstream temperature is equal to the cooling medium temperature.
- Equal to 0, there is no heat transfer to the cooling medium. The downstream temperature is equal to the upstream temperature.

The block assumes no pressure drop. To model pressure losses, use a Flow Restriction block.

Equations

The Heat Exchanger block implements equations that use these variables.

T_{upstr}	Upstream temperature
T_{dnstr}	Downstream temperature
T_{cool}	Cooling medium temperature
$T_{cool, cnst}$	Constant cooling medium temperature
$T_{cool, input}$	External input cooling medium temperature
ϵ	Heat exchanger effectiveness
ϵ_{cnst}	Constant heat exchanger effectiveness
ϵ_{input}	Input heat exchanger effectiveness
c_p	Specific heat at constant pressure
q_{ht}	Heat exchanger heat transfer rate
$p_{flw, in}$	Pressure at inlet
$p_{vol, out}$	Pressure at outlet
$T_{vol, out}$	Temperature at outlet
$h_{vol, out}$	Specific enthalpy at outlet

q_{in}	Heat flow rate at inlet
q_{out}	Heat flow rate at outlet
\dot{m}	Heat exchanger mass flow rate
$T_{flw,in}$	Temperature at inlet
T_{in}	Heat exchanger inlet temperature
T_{out}	Heat exchanger outlet temperature
h_{in}	Inlet specific enthalpy

Heat Exchanger Effectiveness

Heat exchanger effectiveness measures the effectiveness of heat transfer from the incoming hot fluid to the cooling medium:

$$\varepsilon = \frac{T_{upstr} - T_{dnstr}}{T_{upstr} - T_{cool}}$$

In an ideal heat exchanger, the downstream temperature equals the cooling temperature. The effectiveness is equal to 1.

$$T_{dnstr} = T_{cool}$$

$$\varepsilon = 1$$

The Heat Exchanger block uses the effectiveness to determine the downstream temperature and heat transfer rate.

$$T_{dnstr} = T_{upstr} - \varepsilon(T_{upstr} - T_{cool})$$

$$q_{ht} = \dot{m}c_p(T_{upstr} - T_{dnstr})$$

Fluid Flow

Since the block assumes no pressure drop, $P_{flw,in} = P_{vol,out}$.

The flow component connection to the heat exchanger inlet determines the direction of the mass flow. Based on the mass flow rate direction, these temperature and heat flow equations apply.

Fluid Flow	Mass Flow Rate	Temperatures and Heat Flow
Forward — From engine flow component to outlet volume	$\dot{m} \geq 0$	$T_{upstr} = T_{flw,in}$ $T_{in} = T_{upstr}$ $T_{out} = T_{dnstr}$ $q_{out} = \dot{m}c_p T_{dnstr}$
Reverse — From outlet volume to engine flow component	$\dot{m} < 0$	$T_{upstr} = T_{vol,out}$ $T_{in} = T_{dnstr}$ $T_{out} = T_{vol,out}$ $h_{in} = c_p T_{dnstr}$ $q_{out} = \dot{m}h_{vol,out}$

The block uses the internal signal `FlwDir` to track the direction of the flow.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks	PwrHeatFlw In	Heat flow rate at port C q_{in}
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrHeatFlw Out	Heat flow rate at port B $-q_{out}$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrHeatTrn sfr	Heat transfer rate to cooling medium $-q_{ht}$
	PwrStored — Stored energy rate of change		<i>Not used</i>
	<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 		

Ports

Input

C — Inlet mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing the heat exchanger:

- MassFlwRate — Mass flow rate at inlet, \dot{m} , in kg/s
- HeatFlwRate — Heat flow rate at inlet, q_{in} , in J/s
- Temp — Temperature at inlet, $T_{flw,in}$, in K
- MassFrac — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide

- `NOxMassFrac` — Nitric oxide and nitrogen dioxide
- `PmMassFrac` — Particulate matter
- `AirMassFrac` — Air
- `BrndGasMassFrac` — Burned gas

B — Outlet volume pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the heat exchanger:

- `Prs` — Pressure at outlet, $p_{vol, out}$, in Pa
- `Temp` — Temperature at outlet, $T_{vol, out}$, in K
- `Enth` — Specific enthalpy at outlet, $h_{vol, out}$, in J/kg
- `MassFrac` — Outlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- `O2MassFrac` — Oxygen
- `N2MassFrac` — Nitrogen
- `UnbrndFuelMassFrac` — Unburned fuel
- `CO2MassFrac` — Carbon dioxide
- `H2OMassFrac` — Water
- `COMassFrac` — Carbon monoxide
- `NOMassFrac` — Nitric oxide
- `NO2MassFrac` — Nitrogen dioxide
- `NOxMassFrac` — Nitric oxide and nitrogen dioxide
- `PmMassFrac` — Particulate matter
- `AirMassFrac` — Air
- `BrndGasMassFrac` — Burned gas

Effct — Heat exchanger effectiveness

scalar

Heat exchanger effectiveness, ϵ_{input} .

Dependencies

To create this port, set **Effectiveness model** to External input.

CoolTemp — Cooling medium temperature

scalar

Cooling medium temperature, $T_{cool, input}$.

Dependencies

To create this port, set **Cooling medium temperature input** to External input

Output

Info — Heat exchanger data

bus

Bus signal containing these block calculations.

Signal		Description	Units	
InletTemp		Heat exchanger inlet temperature	K	
OutletTemp		Heat exchanger outlet temperature	K	
HeatTrnsfrRate		Heat exchanger heat transfer rate	J/s	
PwrInfo	PwrTrnsfrd	PwrHeatFlwIn	Heat flow rate at port C	W
		PwrHeatFlwOut	Heat flow rate at port B	W
	PwrNotTrnsfrd	PwrHeatTrnsfr	Heat transfer rate to cooling medium	W
	PwrStored		<i>Not used</i>	

C — Inlet flow pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the heat exchanger:

- Prs — Pressure at inlet, $p_{flw,in}$, in Pa
- Temp — Temperature at inlet, T_{in} , in K
- Enth — Specific enthalpy at inlet, h_{in} , in J/kg
- MassFrac — Inlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

B – Outlet volume mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing the heat exchanger:

- **MassFlwRate** — Mass flow rate at outlet, \dot{m} , in kg/s
- **HeatFlwRate** — Heat flow rate at outlet, q_{out} , in J/s
- **Temp** — Temperature at outlet, T_{out} , in K
- **MassFrac** — Outlet mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- **O2MassFrac** — Oxygen
- **N2MassFrac** — Nitrogen
- **UnbrndFuelMassFrac** — Unburned fuel
- **CO2MassFrac** — Carbon dioxide
- **H2OMassFrac** — Water
- **COMassFrac** — Carbon monoxide
- **NOMassFrac** — Nitric oxide
- **NO2MassFrac** — Nitrogen dioxide
- **NOxMassFrac** — Nitric oxide and nitrogen dioxide
- **PmMassFrac** — Particulate matter
- **AirMassFrac** — Air
- **BrndGasMassFrac** — Burned gas

Parameters**Block Options****Effectiveness model — Model type for heat effectiveness**

Constant (default) | External input

Type of model to calculate the heat exchanger effectiveness.

Dependencies

Selecting:

- `External input` creates the `Effct` port.
- `Constant` enables the **Heat exchanger effectiveness**, `ep_cnst` parameter.

Cooling medium temperature input — Specify type

Constant (default) | External input

Cooling medium temperature input.

Dependencies

Selecting:

- External input creates the CoolTemp port.
- Constant enables the **Cooling medium temperature, T_cool_cnst** parameter.

Image type — Icon color

Intercooler (default) | EGR cooler hot to cold | EGR cooler cold to hot

Block icon color:

- Intercooler for blue, to indicate an intercooler
- EGR cooler hot to cold for red to blue, to indicate EGR from hot to cold
- EGR cooler cold to hot for blue to red, to indicate EGR from cold to hot

Heat exchanger effectiveness, ep_cnst — Effectiveness

0.7 (default) | scalar

Constant heat exchanger effectiveness, ϵ_{cnst} .

Dependencies

To enable this parameter, select Constant for the **Effectiveness model** parameter.

Cooling medium temperature, T_cool_cnst — Temperature

300 (default) | scalar

Constant cooling medium temperature, $T_{cool, cnst}$, in K.

Dependencies

To enable this parameter, select Constant for the **Cooling medium temperature input** parameter.

Specific heat at constant pressure, cp — Specific heat

1005 (default) | scalar

Specific heat at constant pressure, c_p , in J/(kg*K).

Version History

Introduced in R2017a

References

- [1] Eriksson, Lars and Nielsen, Lars. *Modeling and Control of Engines and Drivelines*. Chichester, West Sussex, United Kingdom: John Wiley & Sons Ltd, 2014.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

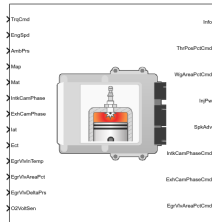
See Also

Control Volume System | Flow Restriction

SI Controller

Spark-ignition engine controller that uses the driver torque request

Library: Powertrain Blockset / Propulsion / Combustion Engine Controllers



Description

The SI Controller block implements a spark-ignition (SI) controller that uses the driver torque request to calculate the open-loop air, fuel, and spark actuator commands that are required to meet the driver demand.

You can use the SI Controller block in engine control design or performance, fuel economy, and emission tradeoff studies. The core engine, throttle, and turbocharger wastegate subsystems require the commands that are output from the SI Controller block.

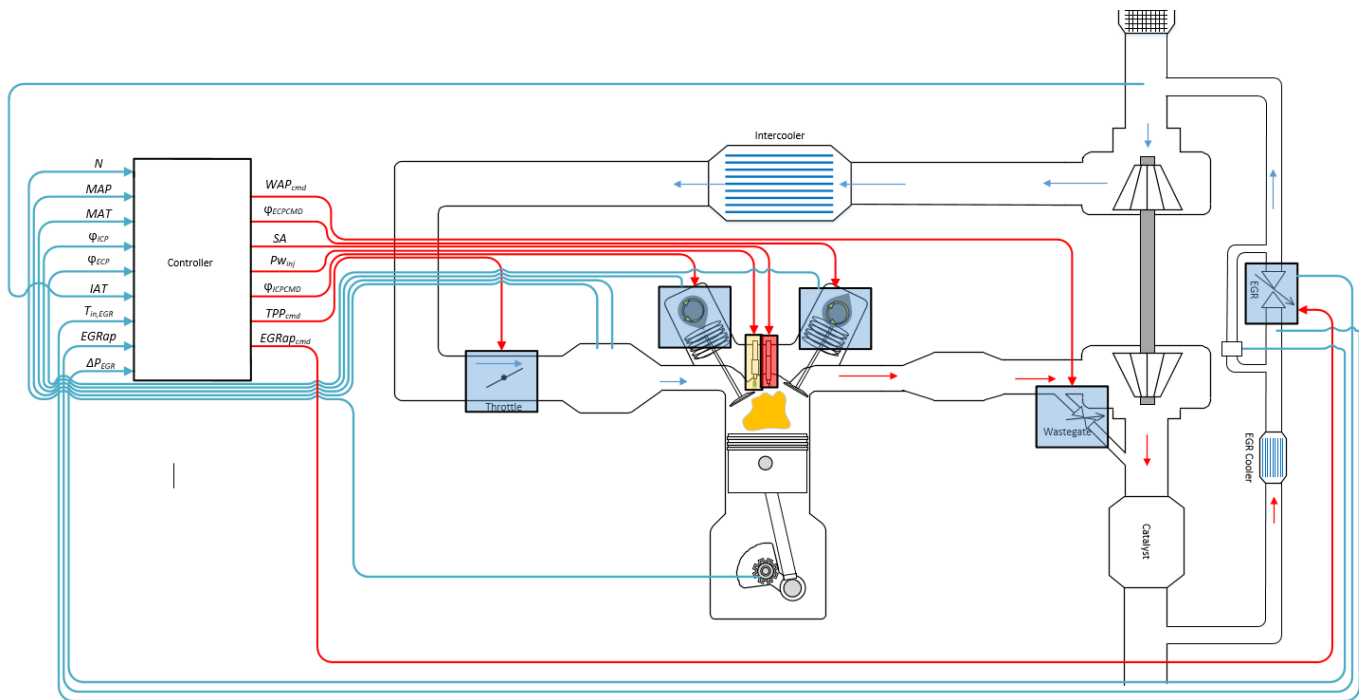
The block uses the commanded torque and engine speed to determine these open-loop actuator commands:

- Throttle position percent
- Wastegate area percent
- Injector pulse-width
- Spark advance
- Intake cam phaser angle
- Exhaust cam phaser angle
- Exhaust gas recirculation (EGR) valve area percent

The SI Controller block has two subsystems:

- The **Controller** subsystem — Determines the commands based on the commanded torque, measured engine speed, and estimated cylinder air mass.
- The **Estimator** subsystem — Determines the estimated air mass flow, torque, and exhaust gas temperature from intake manifold gas pressure, intake manifold gas temperature, engine speed, and cam phaser positions.

The figure illustrates the signal flow.



The figure uses these variables.

N	Engine speed
MAP	Cycle average intake manifold pressure
IAT	Intake air temperature
$T_{in,EGR}$	Temperature at EGR valve inlet
MAT	Cycle average intake manifold gas absolute temperature
$\phi_{ICP}, \phi_{ICPCMD}$	Intake cam phaser angle and intake cam phaser angle command, respectively
ϕ_{ECP}, ϕ_{EPCMD}	Exhaust cam phaser angle and exhaust cam phaser angle command, respectively
$EGRap,$ $EGRap_{cmd}$	EGR valve area percent and EGR valve area percent command, respectively
ΔP_{EGR}	Pressure difference at EGR valve inlet and outlet
WAP_{cmd}	Turbocharger wastegate area percent command
SA	Spark advance
Pw_{inj}	Fuel injector pulse-width
TPP_{cmd}	Throttle position percent command

The Model-Based Calibration Toolbox was used to develop the tables that are available with the Powertrain Blockset.

Controller

Air

The block determines the commanded engine load (that is, normalized cylinder air mass) from a lookup table that is a function of commanded torque and measured engine speed.

$$L_{cmd} = f_{Lcmd}(T_{cmd}, N)$$

To achieve the commanded load, the controller sets the throttle position percent and turbocharger wastegate area percent using feed forward lookup tables. The lookup tables are functions of the commanded load and measured engine speed.

$$TAP_{cmd} = f_{TAPcmd}(L_{cmd}, N)$$

$$TPP_{cmd} = f_{TPPcmd}(TAP_{cmd})$$

$$WAP_{cmd} = f_{WAPcmd}(L_{cmd}, N)$$

To determine the cam phaser angle commands, the block uses lookup tables that are functions of estimated engine load and measured engine speed.

$$\varphi_{ICPCMD} = f_{ICPCMD}(L_{est}, N)$$

$$\varphi_{ECPCMD} = f_{ECPCMD}(L_{est}, N)$$

The block calculates the desired engine load using this equation.

$$L_{est} = \frac{CpsR_{air}T_{std}\dot{m}_{air,est}}{P_{std}V_dN}$$

The equations use these variables.

L_{est}	Estimated engine load
L_{cmd}	Commanded engine load
N	Engine speed
T_{cmd}	Commanded engine torque
TAP_{cmd}	Throttle area percent command
TPP_{cmd}	Throttle position percent command
WAP_{cmd}	Turbocharger wastegate area percent command
Cps	Crankshaft revolutions per power stroke
P_{std}	Standard pressure
T_{std}	Standard temperature
R_{air}	Ideal gas constant for air and burned gas mixture
V_d	Displaced volume
$\dot{m}_{air,est}$	Estimated engine air mass flow

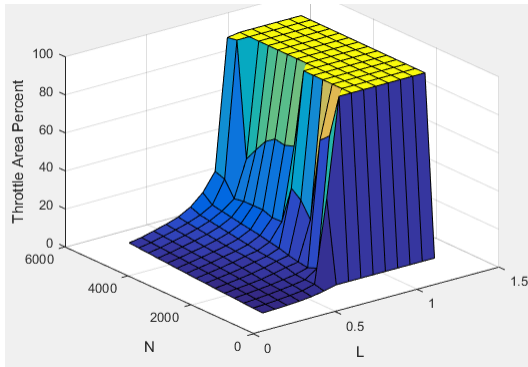
The controller subsystem uses these lookup tables for the air calculations.

- The throttle area percent command lookup table, f_{TAPcmd} , is a function of commanded load and engine speed

$$TAP_{cmd} = f_{TAPcmd}(L_{cmd}, N)$$

where:

- TAP_{cmd} is throttle area percentage command, in percent.
- $L_{cmd}=L$ is commanded engine load, dimensionless.
- N is engine speed, in rpm.



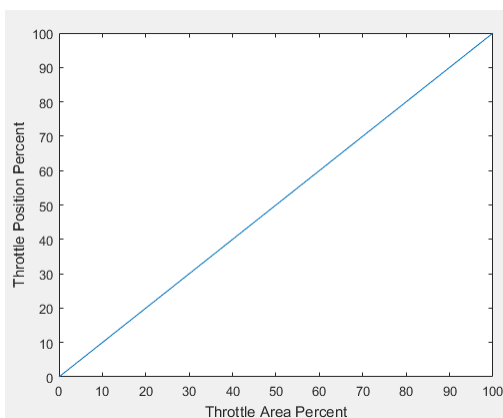
- To account for the non-linearity of the throttle position to throttle area, the throttle position percent lookup table linearizes the open-loop air mass flow control.

The throttle position percent command lookup table, f_{TPPcmd} , is a function of the throttle area percentage command

$$TPP_{cmd} = f_{TPPcmd}(TAP_{cmd})$$

where:

- TPP_{cmd} is throttle position percentage command, in percent.
- TAP_{cmd} is throttle area percentage command, in percent.



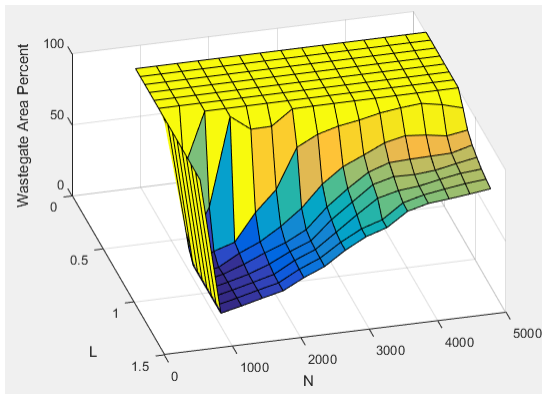
- The wastegate area percent command lookup table, f_{WAPcmd} , is a function of the commanded engine load and engine speed

$$WAP_{cmd} = f_{WAPcmd}(L_{cmd}, N)$$

where:

- WAP_{cmd} is wastegate area percentage command, in percent.
- $L_{cmd}=L$ is commanded engine load, dimensionless.

- N is engine speed, in rpm.

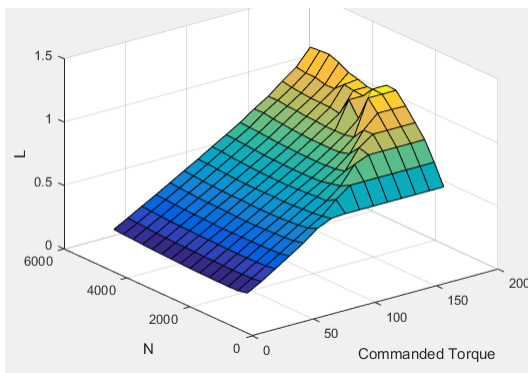


- The commanded engine load lookup table, f_{Lcmd} , is a function of the commanded torque and engine speed

$$L_{cmd} = f_{Lcmd}(T_{cmd}, N)$$

where:

- $L_{cmd}=L$ is commanded engine load, dimensionless.
- T_{cmd} is commanded torque, in N·m.
- N is engine speed, in rpm.

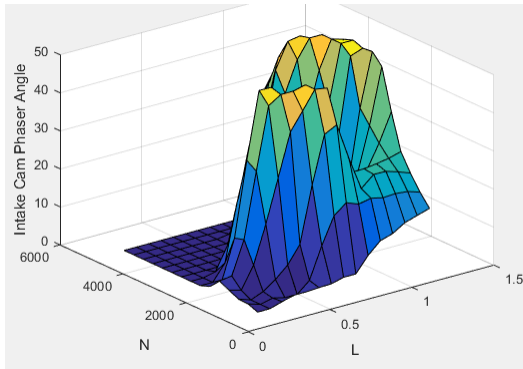


- The intake cam phaser angle command lookup table, f_{ICPCMD} , is a function of the engine load and engine speed

$$\varphi_{ICPCMD} = f_{ICPCMD}(L_{est}, N)$$

where:

- φ_{ICPCMD} is commanded intake cam phaser angle, in degrees crank advance.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.

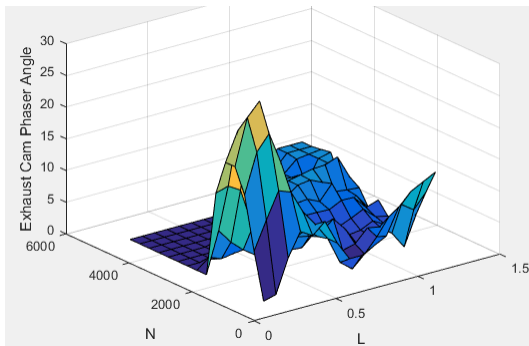


- The exhaust cam phaser angle command lookup table, f_{ECPCMD} , is a function of the engine load and engine speed

$$\varphi_{ECPCMD} = f_{ECPCMD}(L_{est}, N)$$

where:

- φ_{ECPCMD} is commanded exhaust cam phaser angle, in degrees crank retard.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



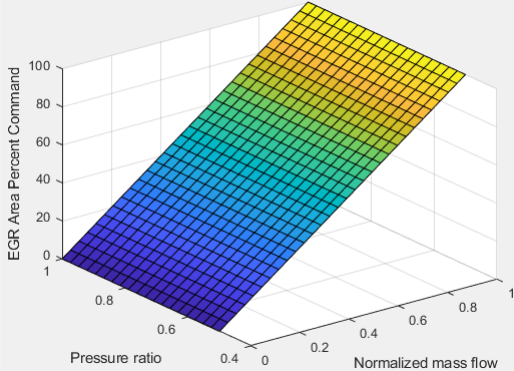
EGR

EGR is typically expressed as a percent of total intake port flow.

$$EGR_{pct} = 100 \frac{\dot{m}_{EGR}}{\dot{m}_{EGR} + \dot{m}_{air}}$$

To calculate the EGR area percent command, the block uses equations and a lookup table.

Equations	$\dot{m}_{EGRstd, cmd} = \dot{m}_{EGR, cmd} \frac{P_{std}}{P_{in, EGR}} \sqrt{\frac{T_{in, EGR}}{T_{std}}}$ $\dot{m}_{EGRstd, max} = f_{EGRstd, max} \left(\frac{P_{out, EGR}}{P_{in, EGR}} \right)$ $\dot{m}_{EGR, cmd} = EGR_{pct, cmd} \dot{m}_{intk, est}$
-----------	---

Lookup table	<p>The EGR area percent command, $EGRap_{cmd}$, lookup table is a function of the normalized mass flow and pressure ratio</p> $EGRap_{cmd} = f_{EGRap,cmd} \left(\frac{\dot{m}_{EGRstd,cmd}}{\dot{m}_{EGRstd,max}}, \frac{P_{out,EGR}}{P_{in,EGR}} \right)$ <p>where:</p> <ul style="list-style-type: none"> • $EGRap_{cmd}$ is commanded EGR area percent, dimensionless. • $\frac{\dot{m}_{EGRstd,cmd}}{\dot{m}_{EGRstd,max}}$ is the normalized mass flow, dimensionless. • $\frac{P_{out,EGR}}{P_{in,EGR}}$ is the pressure ratio, dimensionless. 
--------------	--

The equations and table use these variables.

$EGRap$, $EGRap_{cmd}$	EGR valve area percent and EGR valve area percent command, respectively
$EGR_{pct,cmd}$	EGR percent command
$\dot{m}_{EGRstd,cmd}$	Commanded standard mass flow
$\dot{m}_{EGRstd,max}$	Maximum standard mass flow
$\dot{m}_{EGR,cmd}$	Commanded mass flow
$\dot{m}_{intk,est}$	Estimated intake port mass flow
T_{std}, P_{std}	Standard temperature and pressure
$T_{in,EGR}$	Temperature at EGR valve inlet
$P_{out,EGR}, P_{in,EGR}$	Pressure at EGR valve inlet and outlet, respectively

Fuel

The air-fuel ratio (AFR) impacts three-way-catalyst (TWC) conversion efficiency, torque production, and combustion temperature. The engine controller manages AFR by commanding injector pulse-width from a desired relative AFR. The relative AFR, λ_{cmd} , is the ratio between the commanded AFR and the stoichiometric AFR of the fuel.

$$\lambda_{cmd} = \frac{AFR_{cmd}}{AFR_{stoich}}$$

$$AFR_{cmd} = \frac{\dot{m}_{air,est}}{\dot{m}_{fuel,cmd}}$$

The SI Controller block accounts for the extra fuel delivered to the SI engine during startup. If the engine speed is greater than the startup engine cranking speed, the SI Controller block enriches the optimal AFR, lambda, with an exponentially decaying delta lambda. To initialize the delta lambda, the block uses the engine coolant temperature at startup. The delta lambda exponentially decays to zero based on a time constant that is a function of the engine coolant temperature.

You can configure the block for open-loop and closed-loop AFR control.

To	Use	Controls > Fuel > Closed-loop feedback Parameter Setting
<ul style="list-style-type: none"> Assess the dynamic and steady-state accuracy of the controller airflow estimation and fuel delivery. 	(default) Open-loop control	off
<ul style="list-style-type: none"> Hold the average AFR close to stoichiometric AFR to maintain a high TWC conversion efficiency. 	Closed-loop control	on

Open-Loop Control

To create an input port for the commanded AFR (lambda), on the **Controls > Fuel > Open-loop fuel** pane, select **Input lambda**.

You can manually tune the catalyst for maximum efficiency during open-loop AFR control with or without dither. If you want to implement dither during open-loop control, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Dither**.

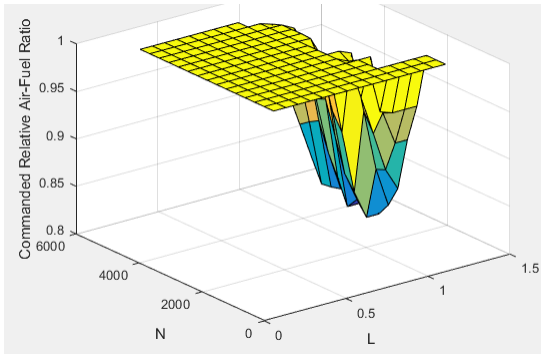
By default, the block is configured to use a lookup table for the commanded AFR.

The commanded lambda, λ_{cmd} , lookup table is a function of estimated engine load and measured engine speed

$$\lambda_{cmd} = f_{\lambda_{cmd}}(L_{est}, N)$$

where:

- λ_{cmd} is commanded relative AFR, dimensionless.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



The block calculates the estimated fuel mass flow rate using the commanded lambda, λ_{cmd} , stoichiometric AFR, and estimated air mass flow rate.

$$\dot{m}_{fuel,cmd} = \frac{\dot{m}_{air,est}}{AFR_{cmd}} = \frac{\dot{m}_{air,est}}{\lambda_{cmd}AFR_{stoich}}$$

The block assumes that the battery voltage and fuel pressure are at nominal settings where pulse-width correction is not necessary. The commanded fuel injector pulse-width is proportional to the fuel mass per injection. The fuel mass per injection is calculated from the commanded fuel mass flow rate, engine speed, and the number of cylinders.

$$Pw_{inj} = \begin{cases} \frac{\dot{m}_{fuel,cmd} Cps \left(\frac{60s}{min} \right) \left(\frac{1000mg}{g} \right) \left(\frac{1000g}{kg} \right)}{NS_{inj} N_{cyl}} & \text{when } Trq_{cmd} > 0 \\ 0 & \text{when } Trq_{cmd} \leq 0 \end{cases}$$

Closed-Loop Control

TWC converters are most efficient when the exhaust AFR is near the stoichiometric AFR, where the air and fuel burn most completely. Around this ideal point, the AFR is within the *catalyst window* in which the catalyst is most efficient at converting carbon monoxide, hydrocarbons, and nitrogen oxides to non-harmful exhaust products. Empirical studies show that oscillating the AFR around stoichiometry at an optimized AFR frequency, amplitude, and bias widens the TWC window, increasing catalyst conversion efficiency in the presence of unavoidable disturbances.

To keep production hardware costs down, AFR control systems include inexpensive switching oxygen sensors positioned in the engine exhaust stream upstream and downstream of the catalyst. The oxygen sensors have a narrow range. Essentially, they switch between too lean (i.e., more air is available than is required to burn the available fuel) and too rich (i.e., more air is available than is required to burn the available fuel).

The block implements a period-based method to control the average AFR at a value within the catalyst window for maximum conversion efficiency. Period-based AFR control is independent of the transport delay across the engine from the fuel injection point to the sensor measurement point. For more information about the method, see *Developing a Period-Based Air-Fuel Ratio Controller Using a Low-Cost Switching Sensor*.

Spark

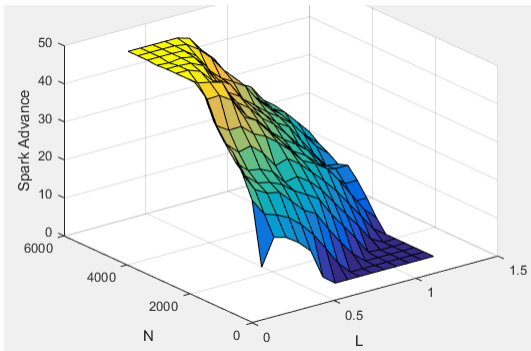
Spark advance is the crank angle before top dead center (BTDC) of the power stroke when the spark is delivered. The spark advance has an impact on engine efficiency, torque, exhaust temperature, knock, and emissions.

The spark advance lookup table is a function of estimated load and engine speed.

$$SA = f_{SA}(L_{est}, N)$$

where:

- SA is spark advance, in crank advance degrees.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



The equations use these variables.

L_{est}	Estimated engine load, based on normalized cylinder air mass
N	Engine speed
f_{SA}	Lookup table for spark advance
SA	Spark advance

Idle Speed

When the commanded torque is below a threshold value, the idle speed controller regulates the engine speed.

If	Idle Speed Controller
$Trq_{cmd,input} < Trq_{idlecmd,enable}$	Enabled
$Trq_{idlecmd,enable} \leq Trq_{cmd,input}$	Not enabled

The idle speed controller uses a discrete PI controller to regulate the target idle speed by commanding a torque.

The PI controller uses this transfer function:

$$C_{idle}(z) = K_{p, idle} + K_{i, idle} \frac{t_s}{z-1}$$

The idle speed commanded torque must be less than the maximum commanded torque:

$$0 \leq Trq_{idlecmd} \leq Trq_{idlecmd,max}$$

Idle speed control is active under these conditions. If the commanded input torque drops below the threshold for enabling the idle speed controller ($Trq_{cmd,input} < Trq_{idlecmd,enable}$), the commanded engine torque is given by:

$$Trq_{cmd} = \max(Trq_{cmd,input}, Trq_{idlecmd}).$$

The equations use these variables.

Trq_{cmd}	Commanded engine torque
$Trq_{cmd,input}$	Input commanded engine torque
$Trq_{idlecmd,enable}$	Threshold for enabling idle speed controller
$Trq_{idlecmd}$	Idle speed controller commanded torque
$Trq_{idlecmd,max}$	Maximum commanded torque
N_{idle}	Base idle speed
$K_{p,idle}$	Idle speed controller proportional gain
$K_{i,idle}$	Idle speed controller integral gain

Speed Limiter

To prevent over revving the engine, the block implements an engine speed limit controller that limits the engine speed to the value specified by the **Rev-limiter speed threshold** parameter on the **Controls > Idle Speed** tab.

If the engine speed, N , exceeds the engine speed limit, N_{lim} , the block sets the commanded engine torque to 0.

To smoothly transition the torque command to 0 as the engine speed approaches the speed limit, the block implements a lookup table multiplier. The lookup table multiplies the torque command by a value that ranges from 0 (engine speed exceeds limit) to 1 (engine speed does not exceed the limit).

Estimator

The estimator subsystem determines the estimated air mass flow, torque, EGR mass flow, and exhaust temperature based on sensor feedback and calibration parameters.

$\dot{m}_{air,est}$	Estimated engine air mass flow
Trq_{est}	Estimated engine torque
$T_{exh,est}$	Estimated engine exhaust temperature
$\dot{m}_{EGR,est}$	Estimated low-pressure EGR mass flow

Air Mass Flow

To calculate engine air mass flow, configure the SI engine to use either of these air mass flow models.

Air Mass Flow Model	Description
“SI Engine Speed-Density Air Mass Flow Model”	Uses the speed-density equation to calculate the engine air mass flow, relating the engine air mass flow to the intake manifold pressure and engine speed. Consider using this air mass flow model in engines with fixed valvetrain designs.

Air Mass Flow Model	Description
"SI Engine Dual-Independent Cam Phaser Air Mass Flow Model"	<p>To calculate the engine air mass flow, the dual-independent cam phaser model uses:</p> <ul style="list-style-type: none"> • Empirical calibration parameters developed from engine mapping measurements • Desktop calibration parameters derived from engine computer-aided design (CAD) data <p>In contrast to typical embedded air mass flow calculations based on direct air mass flow measurement with an air mass flow (MAF) sensor, this air mass flow model offers:</p> <ul style="list-style-type: none"> • Elimination of MAF sensors in dual cam-phased valvetrain applications • Reasonable accuracy with changes in altitude • Semiphysical modeling approach • Bounded behavior • Suitable execution time for electronic control unit (ECU) implementation • Systematic development of a relatively small number of calibration parameters

To determine the estimated air mass flow, the block uses the intake air mass fraction. The EGR mass fraction at the intake port lags the mass fraction near the EGR valve outlet. To model the lag, the block uses a first order system with a time constant.

$$y_{intk,EGR,est} = \frac{\dot{m}_{EGR,est}}{\dot{m}_{intk,est}} \frac{t_s z}{\tau_{EGR} z + t_s - \tau_{EGR}}$$

The remainder of the gas is air.

$$y_{intk,air,est} = 1 - y_{intk,EGR,est}$$

The equations use these variables.

$y_{intk,EGR,est}$	Estimated intake manifold EGR mass fraction
$y_{intk,air,est}$	Estimated intake manifold air mass fraction
$\dot{m}_{EGR,est}$	Estimated low-pressure EGR mass flow
$\dot{m}_{intk,est}$	Estimated intake port mass flow
τ_{EGR}	EGR time constant

Torque

To calculate the brake torque, configure the SI engine to use either of these torque models.

Brake Torque Model	Description
“SI Engine Torque Structure Model”	<p>For the structured brake torque calculation, the SI engine uses tables for the inner torque, friction torque, optimal spark, spark efficiency, and lambda efficiency.</p> <p>If you select Crank angle pressure and torque on the block Torque tab, you can:</p> <ul style="list-style-type: none"> • Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle. • Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals. • Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input. • Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque. • Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.
“SI Engine Simple Torque Model”	<p>For the simple brake torque calculation, the SI engine block uses a torque lookup table map that is a function of engine speed and load.</p>

EGR

The controller estimates low-pressure mass flow, EGR valve inlet pressure, and EGR valve outlet pressure using an algorithm developed by F. Liu and J. Pfeiffer. The estimator requires measured EGR valve differential pressure, EGR valve area percent, intake air temperature, and EGR valve inlet temperature.

To estimate the EGR valve commands, the block uses:

- Equations

$$\dot{m}_{air, std} = \dot{m}_{air, est} \frac{P_{std}}{P_{amb}} \sqrt{\frac{IAT}{T_{std}}}$$

$$P_{in, EGR} = P_{out, EGR} + \Delta P_{EGR}$$

$$\dot{m}_{EGR, est} = \dot{m}_{EGR, std} \frac{P_{in, EGR}}{P_{std}} \sqrt{\frac{T_{std}}{T_{in, EGR}}}$$

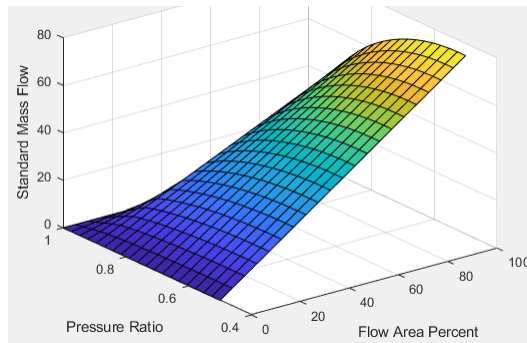
- Tables

- The EGR valve standard mass flow lookup table is a function of EGR valve area percent and the pressure ratio

$$\dot{m}_{EGR, std} = f_{EGR, std} \left(EGRap, \frac{P_{out, EGR}}{P_{in, EGR}} \right)$$

where:

- $\dot{m}_{EGR, std}$ is EGR valve standard mass flow, dimensionless.
- $EGRap$ is EGR valve flow area percent, in percent.
- $\frac{P_{out, EGR}}{P_{in, EGR}}$ is the pressure ratio, dimensionless.

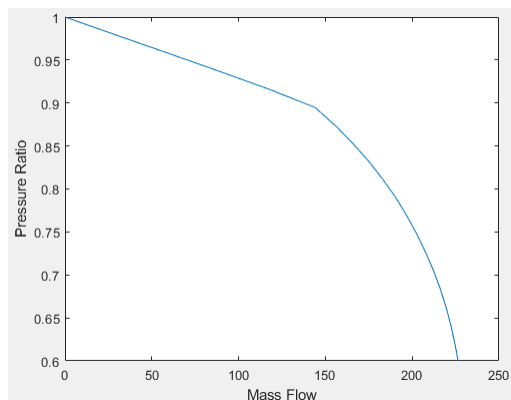


- The pressure ratio is a function of the standard mass flow

$$\frac{P_{out, EGR}}{P_{amb}} = f_{intksys, pr}(\dot{m}_{air, std})$$

where:

- $\dot{m}_{air, std}$ is standard mass flow, in g/s.
- $\frac{P_{out, EGR}}{P_{amb}}$ is pressure ratio, dimensionless.



The equations use these variables.

$EGRap$	EGR valve area percent command
IAT	Intake air temperature

$\dot{m}_{air, std}, \dot{m}_{EGR, std}$	Standard air and EGR valve mass flow, respectively
$\dot{m}_{air, est}, \dot{m}_{EGR, est}$	Estimated air and EGR valve mass flow, respectively
T_{std}, P_{std}	Standard temperature and pressure
T_{amb}, P_{amb}	Ambient temperature and pressure
ΔP_{EGR}	Pressure difference at EGR valve inlet and outlet
$T_{in,EGR}, T_{out,EGR}$	Temperature at EGR valve inlet and outlet, respectively
$P_{in,EGR}, P_{out,EGR}$	Pressure at EGR valve inlet and outlet, respectively

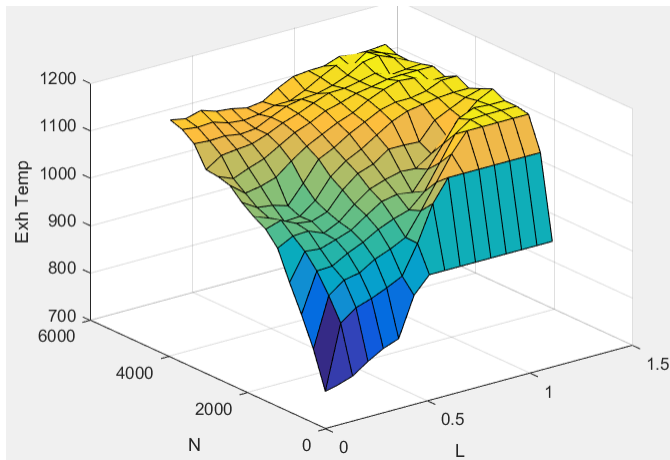
Exhaust Temperature

The exhaust temperature lookup table, f_{Texh} , is a function of engine load and engine speed

$$T_{exh} = f_{Texh}(L, N)$$

where:

- T_{exh} is engine exhaust temperature, in K.
- L is normalized cylinder air mass or engine load, dimensionless.
- N is engine speed, in rpm.



Ports

Input

TrqCmd — Commanded engine torque

scalar

Commanded engine torque, $Trq_{cmd,input}$, in N·m.

EngSpd — Measured engine speed

scalar

Measured engine speed, N , in rpm.

AmbPrs — Measured absolute ambient pressure

scalar

Measured ambient pressure, P_{Amb} , in Pa.**Map — Measured intake manifold absolute pressure**

scalar

Measured intake manifold absolute pressure MAP , in Pa.**Mat — Measured intake manifold absolute temperature**

scalar

Measured intake manifold absolute temperature, MAT , in K.**IntkCamPhase — Intake cam phaser angle**

scalar

Intake cam phaser angle, φ_{ICP} , in degCrkAdv, or degrees crank advance.**ExhCamPhase — Exhaust cam phaser angle**

scalar

Exhaust cam phaser angle, φ_{ECP} , in degCrkRet, or degrees crank retard.**Iat — Intake air temperature**

scalar

Intake air temperature, IAT , in K.**Ect — Engine cooling temperature**

scalar

Engine cooling temperature, $T_{coolant}$, in K.**EgrVlvInTemp — EGR valve inlet temperature**

scalar

EGR valve inlet temperature, $T_{in,EGR}$, in K.**EgrVlvAreaPct — EGR valve area percent**

scalar

EGR valve area percent, $EGRap$, in %.**EgrVlvDeltaPrs — EGR valve delta pressure**

scalar

EGR valve delta pressure, ΔP_{EGR} , in Pa.**O2VltSen — Oxygen sensor voltage**

scalar

Oxygen sensor voltage for closed-loop air-fuel-ratio (lambda) control, in mV.

To configure the block to use closed-loop air-fuel-ratio control, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

LambdaCmd — Commanded AFR, lambda

scalar

Commanded air-fuel-ratio (lambda), λ_{cmd} , dimensionless.

Dependencies

To create this port, on the **Fuel** tab, on the **Open-loop fuel** pane, select **Input lambda**.

IgSw — Ignition switch

Boolean

State of the vehicle ignition switch, dimensionless.

Dependencies

To create this port, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

ESSEnable — Engine Stop-Start Enable

Boolean

Command to enable or disable the stop-start logic, dimensionless.

Dependencies

To create this port, on the **Stop-Start** tab, select **Enable Engine Stop-Start**. Select **External Enable Port**.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable	Units
TrqCmd	Engine torque	Trq_{cmd}	N·m
LdCmd	Commanded load	L_{cmd}	N/A
ThrPosCmd	Throttle area percent command	TAP_{cmd}	%
WgAreaPctCmd	Wastegate area percent command	WAP_{cmd}	%
InjPw	Fuel injector pulse-width	Pw_{inj}	ms
SpkAdv	Spark advance	SA	degBTDC
IntkCamPhaseCmd	Intake cam phaser angle command	φ_{ICPCMD}	degCrkAdv
ExhCamPhaseCmd	Exhaust cam phaser angle command	φ_{ECPCMD}	degCrkRet
EgrVlvAreaPctCmd	Exhaust cam phaser angle command	$EGRap_{cmd}$	%
FuelMassFlwCmd	EGR valve area percent command	$\dot{m}_{fuel, cmd}$	kg/s
AfrCmd	Commanded air-fuel ratio	AFR_{cmd}	N/A

Signal	Description	Variable	Units
EstEngTrq	Estimated engine torque	Trq_{est}	N·m
EstNrmLzdAirCharg	Estimated normalized cylinder air mass	N/A	N/A
EstIntkPortMassFlw	Estimated intake port air mass flow rate	$\dot{m}_{intk, est}$	kg/s
EstIntkAirMassFlw	Estimated air mass flow rate	$\dot{m}_{air, est}$	kg/s
EstEgrMassFlw	Estimated low-pressure EGR mass flow rate	$\dot{m}_{EGR, est}$	kg/s
EstExhManGasTemp	Estimated exhaust manifold gas temperature	$T_{exh, est}$	K
EngRevLimAct	Flag that indicates if rev-limiter control is active	N/A	N/A
ClsdLpFuelMult	Fuel injector pulse-width multiplier for closed-loop AFR control	Pw_{inj_mult}	N/A

ThrPosPctCmd — Throttle area percent command

scalar

Throttle area percent command, TAP_{cmd} .**WgAreaPctCmd — Wastegate area percent command**

scalar

Wastegate area percent command, WAP_{cmd} .**InjPw — Fuel injector pulse-width**

scalar

Fuel injector pulse-width, Pw_{inj} , in ms.**SpkAdv — Spark advance**

scalar

Spark advance, SA , in degrees crank angle before top dead center (degBTDC).**IntkCamPhaseCmd — Intake cam phaser angle command**

scalar

Intake cam phaser angle command, φ_{ICPCMD} .**ExhCamPhaseCmd — Exhaust cam phaser angle command**

scalar

Exhaust cam phaser angle command, φ_{ECPCMD} .**EgrVlvAreaPctCmd — EGR valve area percent command**

scalar

EGR valve area percent command, $EGRap_{cmd}$, in %.

Parameters

Configuration

Air mass flow estimation model — Select air mass flow estimation model

Dual Variable Cam Phasing (default) | Simple Speed-Density

To calculate engine air mass flow, configure the SI engine to use either of these air mass flow models.

Air Mass Flow Model	Description
"SI Engine Speed-Density Air Mass Flow Model"	Uses the speed-density equation to calculate the engine air mass flow, relating the engine air mass flow to the intake manifold pressure and engine speed. Consider using this air mass flow model in engines with fixed valvetrain designs.
"SI Engine Dual-Independent Cam Phaser Air Mass Flow Model"	<p>To calculate the engine air mass flow, the dual-independent cam phaser model uses:</p> <ul style="list-style-type: none"> • Empirical calibration parameters developed from engine mapping measurements • Desktop calibration parameters derived from engine computer-aided design (CAD) data <p>In contrast to typical embedded air mass flow calculations based on direct air mass flow measurement with an air mass flow (MAF) sensor, this air mass flow model offers:</p> <ul style="list-style-type: none"> • Elimination of MAF sensors in dual cam-phased valvetrain applications • Reasonable accuracy with changes in altitude • Semiphysical modeling approach • Bounded behavior • Suitable execution time for electronic control unit (ECU) implementation • Systematic development of a relatively small number of calibration parameters

Dependencies

The table summarizes the parameter dependencies.

Air Mass Flow Estimation Model	Enables Parameters on Estimation > Air Tab
Dual Variable Cam Phasing	<p>Cylinder volume at intake valve close table, f_{vivc}</p> <p>Cylinder volume intake cam phase breakpoints, $f_{vivc_icp_bpt}$</p> <p>Cylinder trapped mass correction factor, f_{tm_corr}</p> <p>Normalized density breakpoints, $f_{tm_corr_nd_bpt}$</p> <p>Engine speed breakpoints, $f_{tm_corr_n_bpt}$</p> <p>Air mass flow, f_{mdot_air}</p> <p>Exhaust cam phase breakpoints, $f_{mdot_air_ecp_bpt}$</p> <p>Trapped mass flow breakpoints, $f_{mdot_trpd_bpt}$</p> <p>Air mass flow correction factor, $f_{mdot_air_corr}$</p> <p>Engine load breakpoints for air mass flow correction, $f_{mdot_air_corr_ld_bpt}$</p> <p>Engine speed breakpoints for air mass flow correction, $f_{mdot_air_n_bpt}$</p>
Simple Speed-Density	<p>Speed-density volumetric efficiency, f_{nv}</p> <p>Speed-density intake manifold pressure breakpoints, $f_{nv_prs_bpt}$</p> <p>Speed-density engine speed breakpoints, $f_{nv_n_bpt}$</p>

Torque estimation model – Select torque estimation model

Torque Structure (default) | Simple Torque Lookup

To calculate the brake torque, configure the SI engine to use either of these torque models.

Brake Torque Model	Description
"SI Engine Torque Structure Model"	<p>For the structured brake torque calculation, the SI engine uses tables for the inner torque, friction torque, optimal spark, spark efficiency, and lambda efficiency.</p> <p>If you select Crank angle pressure and torque on the block Torque tab, you can:</p> <ul style="list-style-type: none"> • Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle. • Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals. • Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input. • Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque. • Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.
"SI Engine Simple Torque Model"	<p>For the simple brake torque calculation, the SI engine block uses a torque lookup table map that is a function of engine speed and load.</p>

Dependencies

The table summarizes the parameter dependencies.

Torque Estimation Model	Enables Parameters on Estimation > Torque Tab
Torque Structure	<p>Inner torque table, f_tq_inr</p> <p>Friction torque table, f_tq_fric</p> <p>Engine temperature modifier on friction torque, f_fric_temp_mod</p> <p>Engine temperature modifier breakpoints, f_fric_temp_bpt</p> <p>Pumping torque table, f_tq_pump</p> <p>Optimal spark table, f_sa_opt</p> <p>Inner torque load breakpoints, f_tq_inr_l_bpt</p> <p>Inner torque speed breakpoints, f_tq_inr_n_bpt</p> <p>Spark efficiency table, f_m_sa</p> <p>Spark retard from optimal, f_del_sa_bpt</p> <p>Lambda efficiency, f_m_lam</p> <p>Lambda breakpoints, f_m_lam_bpt</p>
Simple Torque Lookup	<p>Torque table, f_tq_nl</p> <p>Torque table load breakpoints, f_tq_nl_l_bpt</p> <p>Torque table speed breakpoints, f_tq_nl_n_bpt</p>

Controls

Air

Engine commanded load table, **f_lcmd** – Lookup table

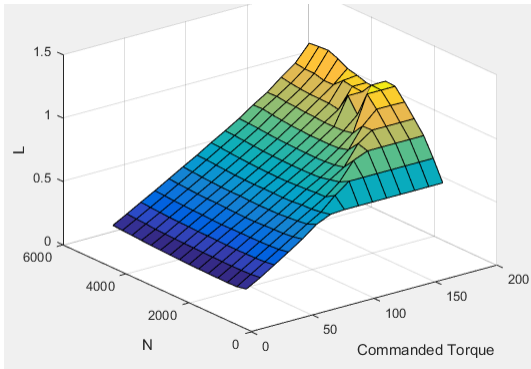
array

The commanded engine load lookup table, f_{Lcmd} , is a function of the commanded torque and engine speed

$$L_{cmd} = f_{Lcmd}(T_{cmd}, N)$$

where:

- $L_{cmd}=L$ is commanded engine load, dimensionless.
- T_{cmd} is commanded torque, in N·m.
- N is engine speed, in rpm.



Torque command breakpoints, $f_{lcmd_tq_bpt}$ – Breakpoints

[15 26.43 37.86 49.29 60.71 72.14 83.57 95 106.4 117.9 129.3 140.7 152.1 163.6 175] (default) | vector

Torque command breakpoints, in N·m.

Speed breakpoints, $f_{lcmd_n_bpt}$ – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Speed breakpoints, in rpm.

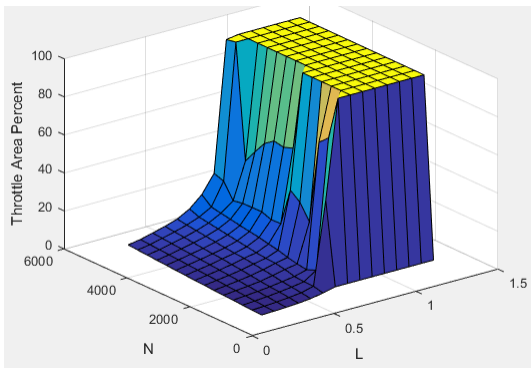
Throttle area percent, f_{tap} – Lookup table, % array

The throttle area percent command lookup table, f_{TAPcmd} , is a function of commanded load and engine speed

$$TAP_{cmd} = f_{TAPcmd}(L_{cmd}, N)$$

where:

- TAP_{cmd} is throttle area percentage command, in percent.
- $L_{cmd}=L$ is commanded engine load, dimensionless.
- N is engine speed, in rpm.



Throttle area percent load breakpoints, $f_{tap_ld_bpt}$ — Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Throttle area percent load breakpoints, dimensionless.

Throttle area percent speed breakpoints, $f_{tap_n_bpt}$ — Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Throttle area percent speed breakpoints, in rpm.

Throttle area percent to position percent table, f_{tpp} — Lookup table

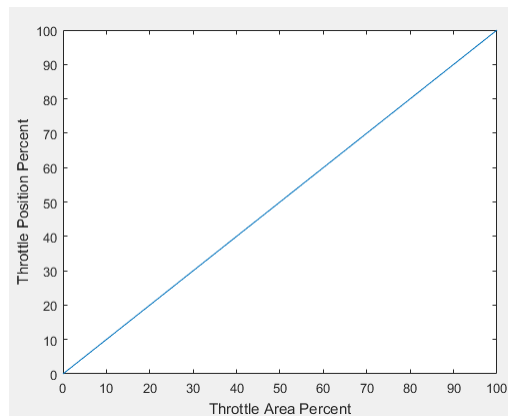
[0 100] (default) | vector

The throttle position percent command lookup table, f_{TPPcmd} , is a function of the throttle area percentage command

$$TPP_{cmd} = f_{TPPcmd}(TAP_{cmd})$$

where:

- TPP_{cmd} is throttle position percentage command, in percent.
- TAP_{cmd} is throttle area percentage command, in percent.

**Throttle area percent to position percent area breakpoints, $f_{tpp_tap_bpt}$ — Breakpoints**

[0 100] (default) | vector

Throttle area percent to position percent area breakpoints, dimensionless.

Wastegate area percent, f_{wap} — Lookup table, %

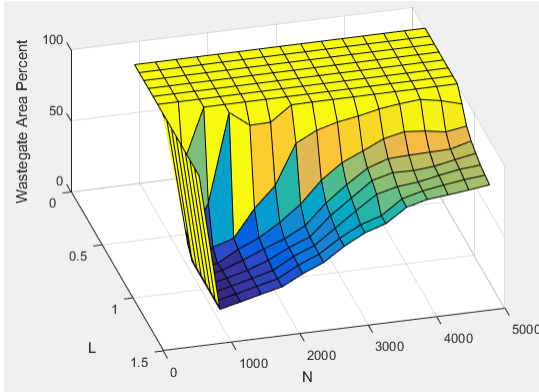
array

The wastegate area percent command lookup table, f_{WAPcmd} , is a function of the commanded engine load and engine speed

$$WAP_{cmd} = f_{WAPcmd}(L_{cmd}, N)$$

where:

- WAP_{cmd} is wastegate area percentage command, in percent.
- $L_{cmd}=L$ is commanded engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, $f_{wap_ld_bpt}$ – Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Load breakpoints, dimensionless.

Speed breakpoints, $f_{wap_n_bpt}$ – Breakpoints, rpm

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Speed breakpoints, in rpm.

Intake cam phaser angle, f_{icp} – Lookup table

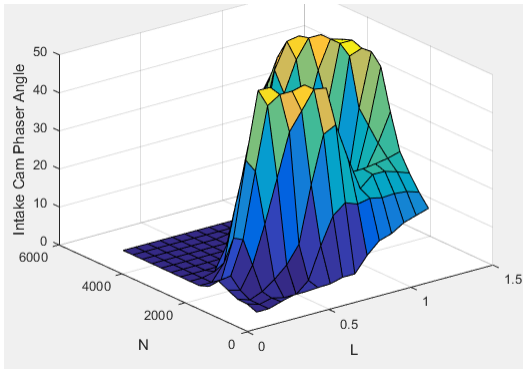
array

The intake cam phaser angle command lookup table, f_{ICPCMD} , is a function of the engine load and engine speed

$$\varphi_{ICPCMD} = f_{ICPCMD}(L_{est}, N)$$

where:

- φ_{ICPCMD} is commanded intake cam phaser angle, in degrees crank advance.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



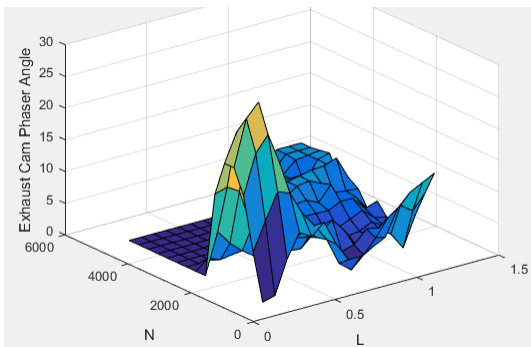
Exhaust cam phaser angle, f_{ecp} – Lookup table array

The exhaust cam phaser angle command lookup table, f_{ECPCMD} , is a function of the engine load and engine speed

$$\varphi_{ECPCMD} = f_{ECPCMD}(L_{est}, N)$$

where:

- φ_{ECPCMD} is commanded exhaust cam phaser angle, in degrees crank retard.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, $f_{cp_ld_bpt}$ – Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Load breakpoints, dimensionless.

Speed breakpoints, $f_{cp_n_bpt}$ – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Speed breakpoints, in rpm.

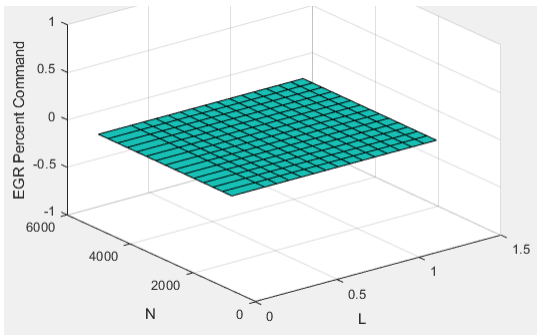
Commanded EGR percent, f_{egrpct_cmd} – Lookup table array

The EGR percent command, $EGR_{pct,cmd}$, lookup table is a function of estimated engine load and engine speed

$$EGR_{pct,cmd} = f_{EGRpct,cmd}(L_{est}, N)$$

where:

- $EGR_{pct,cmd}$ is commanded EGR percent, dimensionless.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, f_egrpct_ld_bpt – Breakpoints

[0 0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Engine load breakpoints, L , dimensionless.

Speed breakpoints, f_egrpct_n_bpt – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Engine speed breakpoints, N , in rpm.

EGR valve area percent, f_egr_areapct_cmd – Lookup table

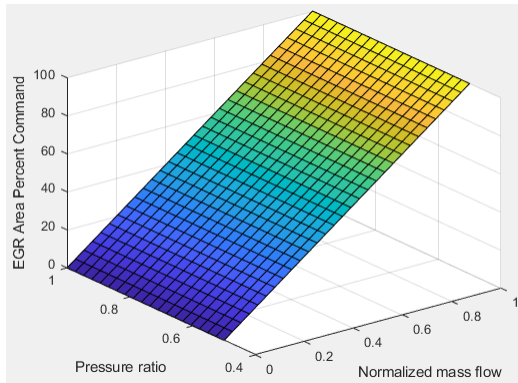
array

The EGR area percent command, $EGRap_{cmd}$, lookup table is a function of the normalized mass flow and pressure ratio

$$EGRap_{cmd} = f_{EGRap,cmd} \left(\frac{\dot{m}_{EGRstd,cmd}}{\dot{m}_{EGRstd,max}}, \frac{P_{out,EGR}}{P_{in,EGR}} \right)$$

where:

- $EGRap_{cmd}$ is commanded EGR area percent, dimensionless.
- $\frac{\dot{m}_{EGRstd,cmd}}{\dot{m}_{EGRstd,max}}$ is the normalized mass flow, dimensionless.
- $\frac{P_{out,EGR}}{P_{in,EGR}}$ is the pressure ratio, dimensionless.



Open EGR valve standard flow, $f_{egr_max_stdflow}$ – Breakpoints

[74.87 74.87 74.74 74.39 73.81 72.98 71.91 70.58 68.97 67.06 64.84 62.25 59.27 55.81 51.79 47.07 36.33 24.22 12.11 0] (default) | vector

Maximum standard EGR valve mass flow breakpoints, $\dot{m}_{EGRstd,max}$, in N·m.

Normalized EGR valve standard flow breakpoints, $f_{egr_areapct_nrmlzdfldw_bpt}$ – Breakpoints

[0 0.03448 0.06897 0.1034 0.1379 0.1724 0.2069 0.2414 0.2759 0.3103 0.3448 0.3793 0.4138 0.4483 0.4828 0.5172 0.5517 0.5862 0.6207 0.6552 0.6897 0.7241 0.7586 0.7931 0.8276 0.8621 0.8966 0.931 0.9655 1] (default) | vector

Normalized mass flow breakpoints, $\frac{\dot{m}_{EGRstd,cmd}}{\dot{m}_{EGRstd,max}}$, dimensionless.

EGR valve pressure ratio breakpoints, $f_{egr_areapct_pr_bpt}$ – Breakpoints

vector

Pressure ratio breakpoints, $\frac{P_{out,EGR}}{P_{in,EGR}}$, dimensionless.

Fuel

Injector slope, S_{inj} – Slope

6.452 (default) | scalar

Fuel injector slope, S_{inj} , in mg/ms.

Stoichiometric air-fuel ratio, afr_stoich – Ratio

14.6 (default) | scalar

Stoichiometric air-fuel ratio, AFR_{stoich} .

Relative air-fuel ratio lambda, f_{lamcmd} – Air-fuel-ratio (AFR) lookup table

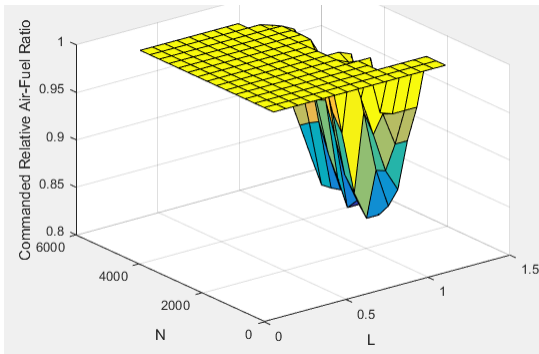
array

The commanded lambda, λ_{cmd} , lookup table is a function of estimated engine load and measured engine speed

$$\lambda_{cmd} = f_{\lambda_{cmd}}(L_{est}, N)$$

where:

- λ_{cmd} is commanded relative AFR, dimensionless.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Load breakpoints, $f_lamcmd_ld_bpt$ – Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Load breakpoints, dimensionless.

Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Speed breakpoints, $f_lamcmd_n_bpt$ – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Speed breakpoints, in rpm.

Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Engine startup lambda enrichment delta vs coolant temperature, $f_startup_lambda_delta$ – Lookup table

[0.5 0.3 0.2 0] (default) | vector

Engine startup lambda enrichment delta as a function of coolant temperature, dimensionless.

The SI Controller block uses this parameter to account for the extra fuel delivered to the spark-ignition (SI) engine during startup. If the engine speed is greater than the **Engine cranking speed** parameter, the SI Controller block enriches the optimal relative air-fuel ratio (lambda) with an exponentially decaying delta lambda. To initialize the delta lambda, the block uses the **Engine startup lambda enrichment delta vs coolant temperature** parameter to create a lambda enrichment table that is a function of the engine coolant temperature. The delta lambda exponentially

decays to zero based on a time constant specified with the **Engine startup lambda enrichment delta time constant vs coolant temperature** parameter.

Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Engine startup lambda enrichment delta time constant vs coolant temperature, f_startup_lambda_delta_timecnst – Lambda time constant

[90 40 12 0] (default) | vector

Engine startup lambda enrichment delta time constant versus coolant temperature, in s.

The SI Controller block uses this parameter to account for the extra fuel delivered to the spark-ignition (SI) engine during startup. If the engine speed is greater than the **Engine cranking speed** parameter, the SI Controller block enriches the optimal relative air-fuel ratio (lambda) with an exponentially decaying delta lambda. To initialize the delta lambda, the block uses the **Engine startup lambda enrichment delta vs coolant temperature** parameter to create a lambda enrichment table that is a function of the engine coolant temperature. The delta lambda exponentially decays to zero based on a time constant specified with the **Engine startup lambda enrichment delta time constant vs coolant temperature** parameter.

Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Engine startup coolant temperature breakpoints, f_startup_ect_bpt – Breakpoints

[-40 0 20 50] (default) | vector

Engine startup coolant temperature breakpoints, in C.

The SI Controller block uses this parameter to account for the extra fuel delivered to the spark-ignition (SI) engine during startup. If the engine speed is greater than the **Engine cranking speed** parameter, the SI Controller block enriches the optimal relative air-fuel ratio (lambda) with an exponentially decaying delta lambda. To initialize the delta lambda, the block uses the **Engine startup lambda enrichment delta vs coolant temperature** parameter to create a lambda enrichment table that is a function of the engine coolant temperature. The delta lambda exponentially decays to zero based on a time constant specified with the **Engine startup lambda enrichment delta time constant vs coolant temperature** parameter.

Dependencies

To create this parameter, on the **Fuel** tab, on the **Open-loop fuel** pane, clear **Input lambda**.

Closed-loop feedback – Minimize commanded AFR error

off (default) | on

Select option to minimize the commanded air-fuel-ratio (lambda), λ_{cmd} error.

Dependencies

Selecting this parameter enables these parameters:

- **Closed-loop fuel proportional gain, ClsdLpFuelPGain**
- **Closed-loop fuel integral gain, ClsdLpFuelIGain**

- **Closed-loop fuel integrator limit, ClsdLpFuelIntgLmt**
- **Lambda dither amplitude, LambdaDitherAmp**
- **Lambda dither frequency, LambdaDitherFrq**
- **Oxygen sensor stoichiometric reset voltage, O2ResetStoichVoltSen**
- **Oxygen sensor minimum voltage reset, O2ResetMinVoltSen**
- **Oxygen sensor maximum voltage reset, O2ResetMaxVoltSen**
- **Oxygen sensor voltage learn update period, O2LearnUpdatePerSen**
- **Oxygen sensor voltage amplitude minimum, O2AmpMinVoltSen**
- **Oxygen sensor ready voltage, O2ReadyVoltSen**
- **Oxygen sensor not ready voltage, O2NotReadyVoltSen**

Dither — Model catalytic conversion efficiency

off (default) | on

Configure the block to model dither. For open-loop analysis, select this option to tune for maximum catalytic conversion efficiency.

Dependencies

By default, selecting **Closed-loop feedback** configures the block to model dither.

To enable this parameter for open-loop air-fuel-ratio (lambda) commands, clear **Closed-loop feedback**.

Selecting this parameter enables these parameters:

- **Lambda dither amplitude, LambdaDitherAmp**
- **Lambda dither frequency, LambdaDitherFrq**

Closed-loop fuel proportional gain, ClsdLpFuelPGain — Proportional gain

0.005 (default) | scalar

Closed-loop fuel proportional gain, dimensionless.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Closed-loop fuel integral gain, ClsdLpFuelIGain — Integral gain

0.05 (default) | scalar

Closed-loop fuel integral gain, dimensionless.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Closed-loop fuel integrator limit, ClsdLpFuelIntgLmt — Integrator limit

0.2 (default) | scalar

Closed-loop fuel integrator limit, dimensionless.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Lambda dither amplitude, LambdaDitherAmp — Amplitude

0.03 (default) | scalar

Lambda dither amplitude, dimensionless.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select either **Closed-loop feedback** or **Dither**.

Lambda dither frequency, LambdaDitherFrq — Frequency

0.75 (default) | scalar

Lambda dither frequency, in Hz.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select either **Closed-loop feedback** or **Dither**.

Oxygen sensor stoichiometric reset voltage, O2ResetStoichVoltSen — Closed-loop AFR control

2500 (default) | scalar

Oxygen sensor stoichiometric reset voltage, O2ResetStoichVoltSen, in mV.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Oxygen sensor minimum voltage reset, O2ResetMinVoltSen — Closed-loop AFR control

0 (default) | scalar

Oxygen sensor minimum voltage reset, O2ResetMinVoltSen, in mV.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Oxygen sensor maximum voltage reset, O2ResetMaxVoltSen — Closed-loop AFR control

5000 (default) | scalar

Oxygen sensor maximum voltage reset, O2ResetMaxVoltSen, in mV.

Dependencies

To enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.

Oxygen sensor voltage learn update period, O2LearnUpdatePerSen — Closed-loop AFR control

4 (default) | scalar

Oxygen sensor voltage learn update period, O2LearnUpdatePerSen, in mV.

DependenciesTo enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.**Oxygen sensor voltage amplitude minimum, O2AmpMinVoltSen — Closed-loop AFR control**

250 (default) | scalar

Oxygen sensor voltage amplitude minimum, O2AmpMinVoltSen, in mV.

DependenciesTo enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.**Oxygen sensor ready voltage, O2ReadyVoltSen — Closed-loop AFR control**

1150 (default) | scalar

Oxygen sensor ready voltage, O2ReadyVoltSen, in mV.

DependenciesTo enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.**Oxygen sensor not ready voltage, O2NotReadyVoltSen — Closed-loop AFR control**

1950 (default) | scalar

Oxygen sensor not ready voltage, O2NotReadyVoltSen, in mV.

DependenciesTo enable this parameter, on the **Fuel** tab, on the **Closed-loop fuel** pane, select **Closed-loop feedback**.**Spark****Spark advance table, f_sa — Lookup table**

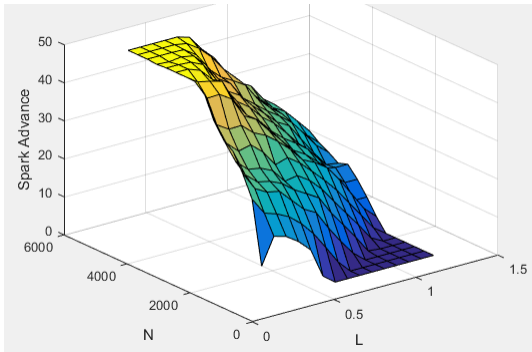
array

The spark advance lookup table is a function of estimated load and engine speed.

$$SA = f_{SA}(L_{est}, N)$$

where:

- SA is spark advance, in crank advance degrees.
- $L_{est}=L$ is estimated engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, $f_{sa_ld_bpt}$ – Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Load breakpoints, dimensionless.

Speed breakpoints, $f_{sa_n_bpt}$ – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Speed breakpoints, in rpm.

Idle Speed

Target idle speed, N_{idle} – Speed

750 (default) | scalar

Target idle speed, N_{idle} , in rpm.

Enable torque command limit, $Trq_{idlecmd_enable}$ – Torque

1 (default) | scalar

Torque to enable the idle speed controller, $Trq_{idlecmd,enable}$, in N·m.

Maximum torque command, $Trq_{idlecmd_max}$ – Torque

50 (default) | scalar

Maximum idle controller commanded torque, $Trq_{idlecmd,max}$, in N·m.

Proportional gain, K_p_{idle} – PI Controller

0.05 (default) | scalar

Proportional gain for idle speed control, $K_{p,idle}$, in N·m/rpm.

Integral gain, K_i_{idle} – PI Controller

0.2 (default) | scalar

Integral gain for idle speed control, $K_{i,idle}$, in N·m/(rpm·s).

Rev-limiter speed threshold – Engine speed limit

scalar

Engine speed limit, N_{lim} , in rpm.

If the engine speed, N , exceeds the engine speed limit, N_{lim} , the block sets the commanded engine torque to 0.

To smoothly transition the torque command to 0 as the engine speed approaches the speed limit, the block implements a lookup table multiplier. The lookup table multiplies the torque command by a value that ranges from 0 (engine speed exceeds limit) to 1 (engine speed does not exceed the limit).

Engine cranking speed, CrankSpeed – Engine speed

150 (default) | scalar

Engine cranking speed, in rpm.

Stop-Start**Enable Engine Stop-Start – Select to enable the engine stop-start logic**

off (default) | on

Select to enable the engine stop-start logic. Selecting this option will activate additional parameters to modify the behavior of the Engine Stop-Start block.

External Enable Port – Create input port

off (default) | on

Select to add a port to the engine controller block which enables or disables the stop-start logic.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Engine stop time, EngStopTime [s] – Engine stop time

5 (default) | scalar

Engine stop time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Catalyst light off time, CatLightOffTime [s] – Catalyst light off time

0 (default) | scalar

Catalyst light off time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Sample time, Ts [s] – Sample time

0.01 (default) | scalar

Sample time for the stop-start logic, in s.

Dependencies

To enable this parameter, on the **Stop-Start** tab, select **Enable Engine Stop-Start**.

Estimation**Air****Number of cylinders, NCyl – Engine cylinders**

4 (default) | scalar

Number of engine cylinders, N_{cyl} .**Crank revolutions per power stroke, Cps – Revolutions per stroke**

2 (default) | scalar

Crankshaft revolutions per power stroke, Cps , in rev/stroke.**Total displaced volume, Vd – Volume**

0.0015 (default) | scalar

Displaced volume, V_d , in m^3 .**Ideal gas constant air, Rair – Constant**

287 (default) | scalar

Ideal gas constant, R_{air} , in $J/(kg \cdot K)$.**Air standard pressure, Pstd – Pressure**

101325 (default) | scalar

Standard air pressure, P_{std} , in Pa.**Air standard temperature, Tstd – Temperature**

293.15 (default) | scalar

Standard air temperature, T_{std} , in K.**Speed-density volumetric efficiency, f_nv – Lookup table**

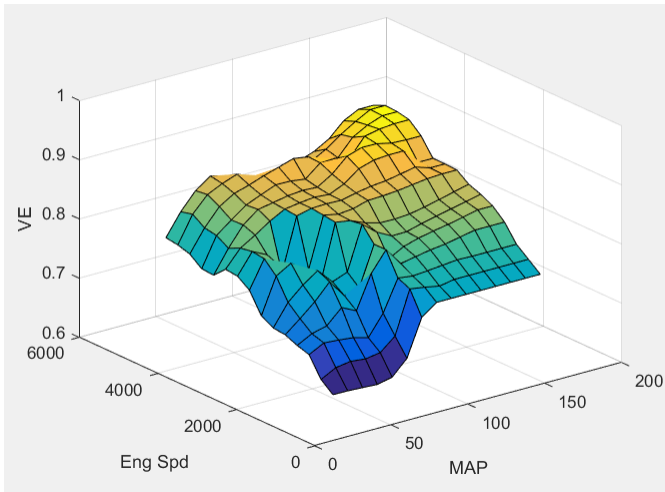
array

The engine volumetric efficiency lookup table, f_{η_v} , is a function of intake manifold absolute pressure and engine speed

$$\eta_v = f_{\eta_v}(MAP, N)$$

where:

- η_v is engine volumetric efficiency, dimensionless.
- MAP is intake manifold absolute pressure, in KPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Simple Speed-Density.

Speed-density intake manifold pressure breakpoints, $f_{nv_prs_bpt}$ – Breakpoints

[31 40.64 50.29 59.93 69.57 79.21 88.86 98.5 108.1 117.8 127.4 137.1 146.7 156.4 166] (default) | vector

Intake manifold pressure breakpoints for speed-density volumetric efficiency lookup table, in KPa.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Simple Speed-Density.

Speed-density engine speed breakpoints, $f_{nv_n_bpt}$ – Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Engine speed breakpoints for speed-density volumetric efficiency lookup table, in rpm.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Simple Speed-Density.

Cylinder volume at intake valve close table, f_{vivc} – 2-D lookup table

array

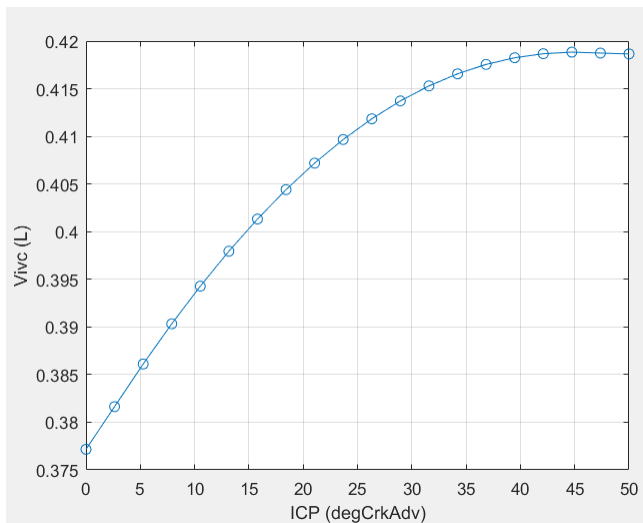
The cylinder volume at intake valve close table (IVC), f_{vivc} is a function of the intake cam phaser angle

$$V_{IVC} = f_{vivc}(\varphi_{ICP})$$

where:

- V_{IVC} is cylinder volume at IVC, in L.

- φ_{ICP} is intake cam phaser angle, in crank advance degrees.



Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Engine speed breakpoints, $f_{tm_corr_n_bpt}$ — Breakpoints

[750 973.7 1197 1421 1645 1868 2092 2316 2539 2763 2987 3211 3434 3658 3882 4105 4329 4553 4776 5000] (default) | vector

Engine speed breakpoints, in rpm.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Cylinder volume intake cam phase breakpoints, $f_{vivc_icp_bpt}$ — Breakpoints

[0 2.632 5.263 7.895 10.53 13.16 15.79 18.42 21.05 23.68 26.32 28.95 31.58 34.21 36.84 39.47 42.11 44.74 47.37 50] (default) | vector

Cylinder volume at intake valve close table breakpoints.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Cylinder trapped mass correction factor, f_{tm_corr} — Lookup table

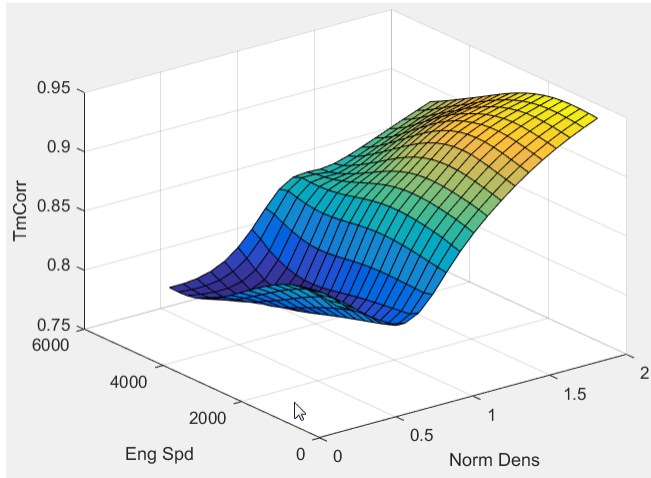
array

The trapped mass correction factor table, f_{TMcorr} , is a function of the normalized density and engine speed

$$TM_{corr} = f_{TMcorr}(\rho_{norm}, N)$$

where:

- TM_{corr} , is trapped mass correction multiplier, dimensionless.
- ρ_{norm} is normalized density, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Normalized density breakpoints, $f_{tm_corr_nd_bpt}$ — Breakpoints

[0.3 0.3895 0.4789 0.5684 0.6579 0.7474 0.8368 0.9263 1.016 1.105 1.195 1.284 1.374 1.463 1.553 1.642 1.732 1.821 1.911 2] (default) | vector

Normalized density breakpoints.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Intake mass flow, f_{mdot_intk} — Lookup table

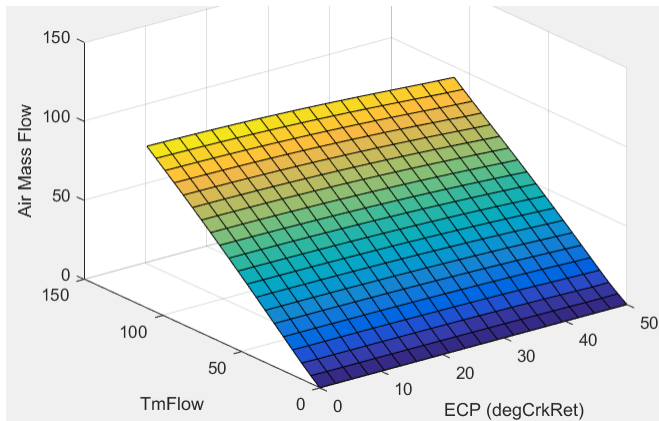
array

The phaser intake mass flow model lookup table is a function of exhaust cam phaser angles and trapped air mass flow

$$\dot{m}_{intkideal} = f_{intkideal}(\varphi_{ECP}, TM_{flow})$$

where:

- $\dot{m}_{intkideal}$ is engine intake port mass flow at arbitrary cam phaser angles, in g/s.
- φ_{ECP} is exhaust cam phaser angle, in degrees crank retard.
- TM_{flow} is flow rate equivalent to corrected trapped mass at the current engine speed, in g/s.



Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Exhaust cam phase breakpoints, $f_mdot_air_ecp_bpt$ — Breakpoints

[0 2.632 5.263 7.895 10.53 13.16 15.79 18.42 21.05 23.68 26.32 28.95 31.58 34.21 36.84 39.47 42.11 44.74 47.37 50] (default) | vector

Exhaust cam phaser breakpoints for air mass flow lookup table.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Trapped mass flow breakpoints, $f_mdot_trpd_bpt$ — Breakpoints

[0 5.79 11.58 17.37 23.16 28.95 34.74 40.53 46.32 52.11 57.89 63.68 69.47 75.26 81.05 86.84 92.63 98.42 104.2 110] (default) | vector

Trapped mass flow breakpoints for air mass flow lookup table.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Air mass flow correction factor, $f_mdot_air_corr$ — Lookup table

array

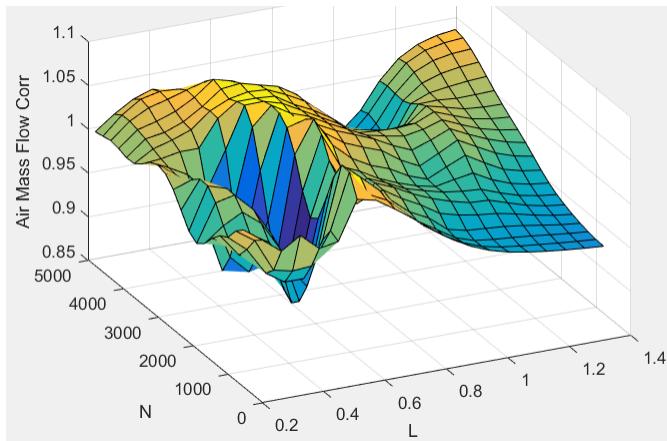
The intake air mass flow correction lookup table, $f_{aircorr}$, is a function of ideal load and engine speed

$$\dot{m}_{air} = \dot{m}_{intkideal} f_{aircorr}(L_{ideal}, N)$$

where:

- L_{ideal} is engine load (normalized cylinder air mass) at arbitrary cam phaser angles, uncorrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.
- \dot{m}_{air} is engine intake air mass flow final correction at steady-state cam phaser angles, in g/s.

- $\dot{m}_{intkideal}$ is engine intake port mass flow at arbitrary cam phaser angles, in g/s.



Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Engine load breakpoints for air mass flow correction, f_mdot_air_corr_ld_bpt – Breakpoints
vector

Engine load breakpoints for air mass flow final correction.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

Engine speed breakpoints for air mass flow correction, f_mdot_air_n_bpt – Breakpoints

[750 973.7 1197 1421 1645 1868 2092 2316 2539 2763 2987 3211 3434 3658 3882 4105 4329 4553 4776 5000] (default) | vector

Engine speed breakpoints for air mass flow final correction.

Dependencies

To enable this parameter, for the **Air mass flow estimation model** parameter, select Dual Variable Cam Phasing.

EGR flow time constant, tau_egr – Constant

0.2 (default) | scalar

EGR flow time constant, τ_{EGR} , in s.

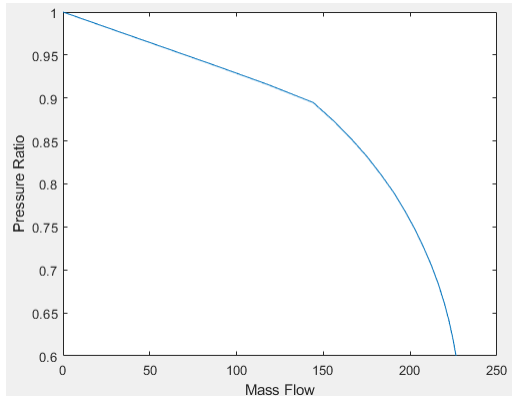
Intake system pressure ratio table, f_intksys_stdflow_pr – Table
array

The pressure ratio is a function of the standard mass flow

$$\frac{P_{out,EGR}}{P_{amb}} = f_{intksys,pr}(\dot{m}_{air,std})$$

where:

- $\dot{m}_{air, std}$ is standard mass flow, in g/s.
- $\frac{P_{out, EGR}}{P_{amb}}$ is pressure ratio, dimensionless.



Standard mass flow rate breakpoints for intake pressure ratio, f_intksys_stdflow_bpt – Breakpoints

[0 29.67 59.34 89.01 117.8 144.1 155.7 166 175.2 183.3 190.7 197 202.7 207.7 212.2 216.1 219.4 222.2 224.5 226.4] (default) | vector

Standard mass flow, $\dot{m}_{air, std}$, in g/s.

EGR valve standard mass flow rate, f_egr_stdflow – Table

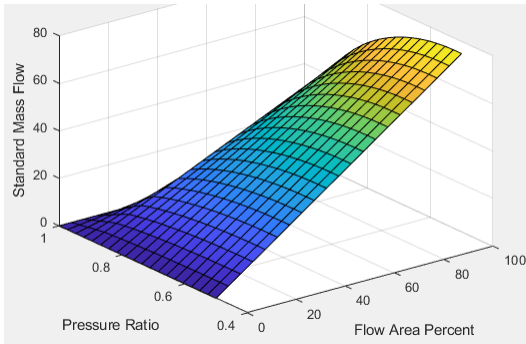
array

The EGR valve standard mass flow lookup table is a function of EGR valve area percent and the pressure ratio

$$\dot{m}_{EGR, std} = f_{EGR, std} \left(EGRap, \frac{P_{out, EGR}}{P_{in, EGR}} \right)$$

where:

- $\dot{m}_{EGR, std}$ is EGR valve standard mass flow, dimensionless.
- $EGRap$ is EGR valve flow area percent, in percent.
- $\frac{P_{out, EGR}}{P_{in, EGR}}$ is the pressure ratio, dimensionless.



EGR valve standard flow pressure ratio breakpoints, `f_egr_stdflow_pr_bpt` – Breakpoints
vector

EGR valve standard flow pressure ratio, $\frac{P_{out,EGR}}{P_{in,EGR}}$, dimensionless.

EGR valve standard flow area percent breakpoints, `f_egr_stdflow_egrp_bpt` – Breakpoints

[0;5;10;15;20;25;30;35;40;45;50;55;60;65;70;75;80;85;90;95;100] (default) | vector

EGR valve flow area percent, $EGRap$, in percent.

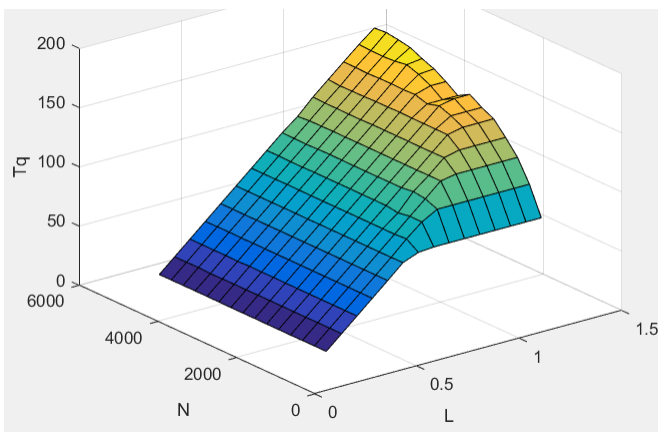
Torque

Torque table, `f_tq_nL` – Lookup table

[L x N] array

For the simple torque lookup table model, the SI engine uses a lookup table map that is a function of engine speed and load, $T_{brake} = f_{TnL}(L, N)$, where:

- T_{brake} is engine brake torque after accounting for spark advance, AFR, and friction effects, in N·m.
- L is engine load, as a normalized cylinder air mass, dimensionless.
- N is engine speed, in rpm.



The simple torque lookup model assumes that the calibration has negative torque values to indicate the non-firing engine load (L) versus speed (N) condition. The calibrated table (L -by- N) contains the non-firing data in the first table row (1 -by- N). When the fuel delivered to the engine is zero, the model uses the data in the first table row (1 -by- N) at or above 100 AFR. 100 AFR results from fuel cutoff or very lean operation where combustion cannot occur.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Torque table load breakpoints, $f_{tq_nl_l_bpt}$ — Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector | [1 x L] vector

Engine load breakpoints, L , dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Torque table speed breakpoints, $f_{tq_nl_n_bpt}$ — Breakpoints

[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default) | vector | [1 x N] vector

Engine speed breakpoints, N , in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Crank angle pressure and torque — Enable Crank angle signals

off (default) | on

If you select **Crank angle pressure and torque** on the block **Torque** tab, you can:

- Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle.
- Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals.
- Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input.
- Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque.
- Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.

Dependencies

To enable this parameter, set **Torque model** to Torque Structure.

Cylinder pressure, f_{crk_prs} — Cylinder pressure table

$L \times M \times N$ array

Cylinder pressure table Prs , as a function of speed N , load L , and crank angle M , in Pa.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Brake torque, f_crk_btq – Brake torque table

$L \times M \times N$ array

Brake torque table T_{brake} , as a function of speed N , load L , and crank angle M , in N·m.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Speed breakpoints, f_crk_n_bpt – Speed breakpoints

[750 5000] (default) | $1 \times N$ vector

Speed breakpoints, N , in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Load breakpoints, f_crk_l_bpt – Load breakpoints

[0.2 1.4] (default) | $1 \times L$ vector

Load breakpoints, L . No dimension.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Crank angle breakpoints, f_crk_ang_bpt – Crank angle breakpoints

[60 660] (default) | $1 \times M$ vector

Crank angle breakpoints, M , in deg.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

TDC compression angles by cylinder, f_crk_tdc_ang – TDC compression angles by cylinder

[0 540 180 360] (default) | vector

Top dead center (TDC) compression angles by cylinder, in deg.

Dependencies

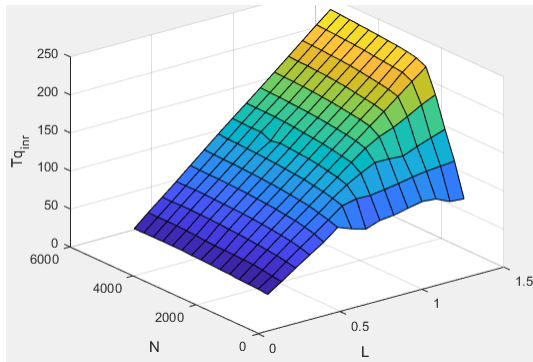
To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Inner torque table, f_{Tq_inr} – Lookup table

array

The inner torque lookup table, f_{Tq_inr} , is a function of engine speed and engine load, $T_{q_inr} = f_{Tq_inr}(L, N)$, where:

- T_{q_inr} is inner torque based on gross indicated mean effective pressure, in N·m.
- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.

**Dependencies**

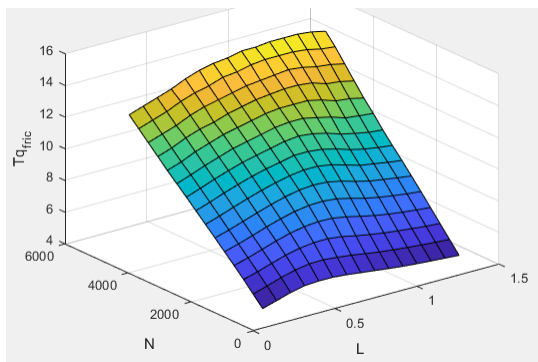
To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Friction torque table, f_{Tq_fric} – Lookup table

array

The friction torque lookup table, f_{Tq_fric} , is a function of engine speed and engine load, $T_{fric} = f_{Tq_fric}(L, N)$, where:

- T_{fric} is friction torque offset to inner torque, in N·m.
- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Engine temperature modifier on friction torque, f_fric_temp_mod – Lookup table

[3.96 3.22 2.56 2.26 2.11 2 1.9 1.83 1.76 1.7 1.65 1.6 1.55 1.49 1.44 1.41
1.38 1.35 1.32 1.3 1.27 1.25 1.24 1.21 1.2 1.18 1.16 1.15 1.13 1.12 1.11 1.1
1.09 1.08 1.07 1.06 1.05 1.05 1.04 1.03 1.02 1.02 1.01 1.01 1 1 1 0.999 0.997
0.995 0.993 0.991 0.989 0.987] (default) | vector | vector

Engine temperature modifier on friction torque, $f_{fric,temp}$, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Engine temperature modifier breakpoints, f_fric_temp_bpt – Breakpoints

[274 276 278 280 282 284 286 288 290 292 294 296 298 300 302 304 306 308 310
312 314 316 318 320 322 324 326 328 330 332 334 336 338 340 342 344 346 348
350 352 354 356 358 360 362 364 366 368 370 372 374 376 378 380] (default) |
vector | vector

Engine temperature modifier breakpoints, in K.

Dependencies

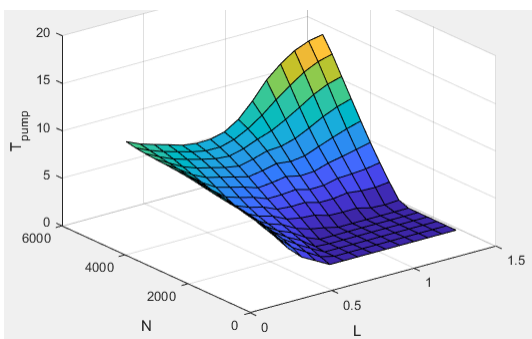
To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Pumping work table, f_tq_pump – Lookup table

array

The pumping work lookup table, $f_{T_{pump}}$, is a function of engine load and engine speed, $T_{pump} = f_{T_{pump}}(L, N)$, where:

- T_{pump} is pumping work, in N·m.
- L is engine load, as a normalized cylinder air mass, dimensionless.
- N is engine speed, in rpm.



Dependencies

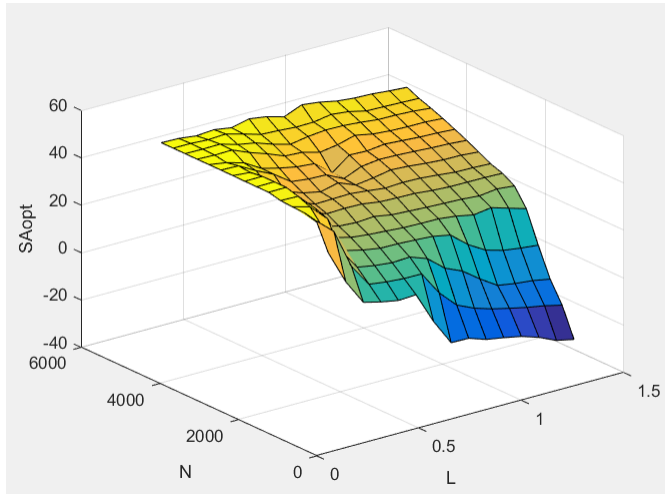
To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Optimal spark table, f_sa_opt – Lookup table

array

The optimal spark lookup table, $f_{SA_{opt}}$, is a function of engine speed and engine load, $SA_{opt} = f_{SA_{opt}}(L, N)$, where:

- SA_{opt} is optimal spark advance timing for maximum inner torque at stoichiometric air-fuel ratio (AFR), in deg.
- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Inner torque load breakpoints, $f_{tq_inr_l_bpt}$ – Breakpoints

[0.2 0.28571 0.37143 0.45714 0.54286 0.62857 0.71429 0.8 0.88571 0.97143 1.0571 1.1429 1.2286 1.3143 1.4] (default) | vector

Inner torque load breakpoints, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Inner torque speed breakpoints, $f_{tq_inr_n_bpt}$ – Breakpoints

[750 1053.5714 1357.1429 1660.7143 1964.2857 2267.8571 2571.4286 2875 3178.5714 3482.1429 3785.7143 4089.2857 4392.8571 4696.4286 5000] (default) | vector

Inner torque speed breakpoints, in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Spark efficiency table, f_{m_sa} – Lookup table

array

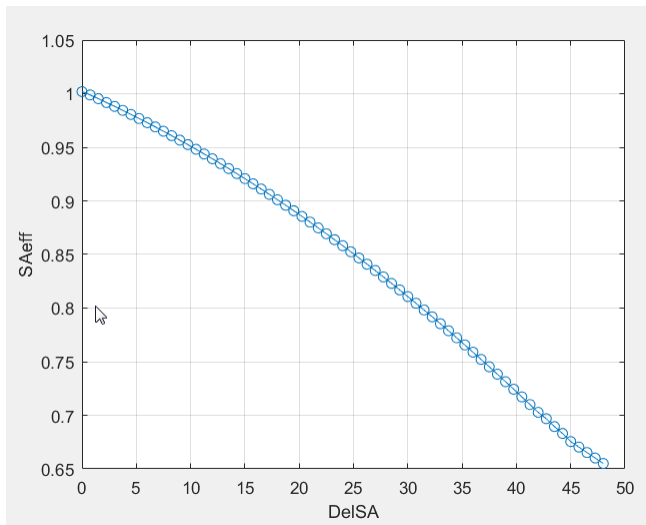
The spark efficiency lookup table, f_{Msa} , is a function of the spark retard from optimal

$$M_{sa} = f_{Msa}(\Delta SA)$$

$$\Delta SA = SA_{opt} - SA$$

where:

- M_{sa} is the spark retard efficiency multiplier, dimensionless.
- ΔSA is the spark retard timing distance from optimal spark advance, in deg.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Spark retard from optimal, `f_del_sa_bpt` – Breakpoints

```
[0 0.75 1.5 2.25 3 3.75 4.5 5.25 6 6.75 7.5 8.25 9 9.75 10.5 11.25 12 12.75
13.5 14.25 15 15.75 16.5 17.25 18 18.75 19.5 20.25 21 21.75 22.5 23.25 24
24.75 25.5 26.25 27 27.75 28.5 29.25 30 30.75 31.5 32.25 33 33.75 34.5 35.25
36 36.75 37.5 38.25 39 39.75 40.5 41.25 42 42.75 43.5 44.25 45 45.75 46.5
47.25 48] (default) | vector
```

Spark retard from optimal inner torque timing breakpoints, in deg.

Dependencies

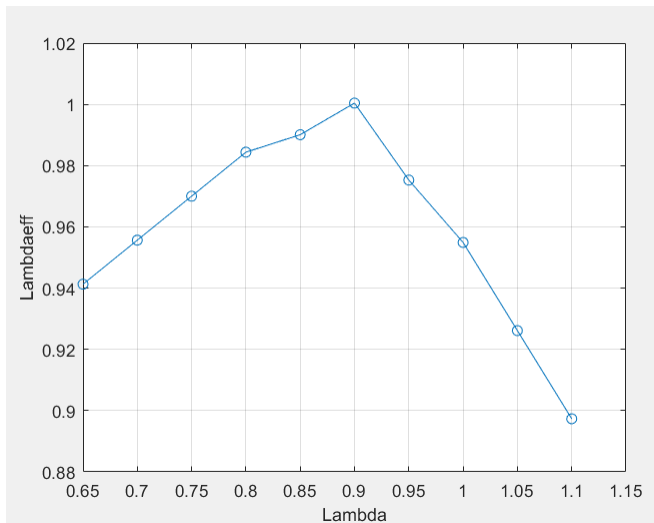
To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Lambda efficiency, `f_m_lam` – Lookup table

array

The lambda efficiency lookup table, $f_{M\lambda}$, is a function of lambda, $M_\lambda = f_{M\lambda}(\lambda)$, where:

- M_λ is the lambda multiplier on inner torque to account for the air-fuel ratio (AFR) effect, dimensionless.
- λ is lambda, AFR normalized to stoichiometric fuel AFR, dimensionless.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Lambda breakpoints, `f_m_lam_bpt` – Breakpoints

[0.65 0.7 0.75 0.8 0.85 0.9 0.95 1 1.05 1.1] (default) | vector

Lambda effect on inner torque lambda breakpoints, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Exhaust

Exhaust temperature table, `f_t_exh` – Lookup table

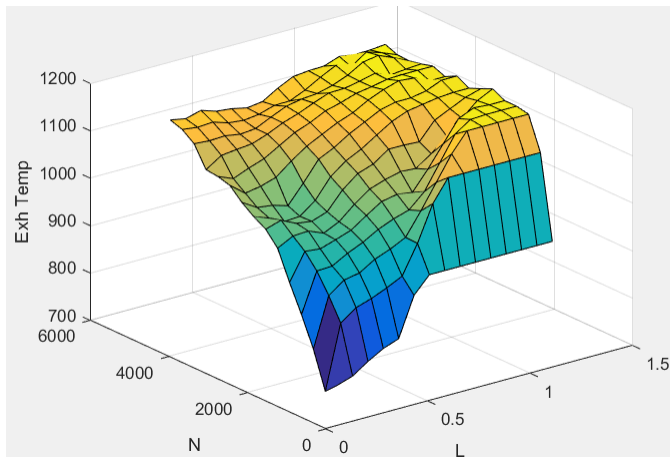
array

The exhaust temperature lookup table, $f_{T_{exh}}$, is a function of engine load and engine speed

$$T_{exh} = f_{T_{exh}}(L, N)$$

where:

- T_{exh} is engine exhaust temperature, in K.
- L is normalized cylinder air mass or engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, `f_t_exh_l_bpt` — Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Engine load breakpoints used for exhaust temperature lookup table.

Speed breakpoints, `f_t_exh_n_bpt` — Breakpoints

[750 1054 1357 1661 1964 2268 2571 2875 3179 3482 3786 4089 4393 4696 5000] (default) | vector

Engine speed breakpoints used for exhaust temperature lookup table, in rpm.

Version History

Introduced in R2017a

References

- [1] Gerhardt, J., Hönninger, H., and Bischof, H., *A New Approach to Functional and Software Structure for Engine Management Systems — BOSCH ME7*. SAE Technical Paper 980801, 1998.
- [2] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.
- [3] Leone, T. Christenson, E., Stein, R., *Comparison of Variable Camshaft Timing Strategies at Part Load*. SAE Technical Paper 960584, 1996, doi:10.4271/960584.
- [4] Liu, F. and Pfeiffer, J., *Estimation Algorithms for Low Pressure Cooled EGR in Spark-Ignition Engines*. SAE Int. J. Engines 8(4):2015, doi:10.4271/2015-01-1620.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

SI Core Engine | Mapped SI Engine

Topics

“Engine Calibration Maps”

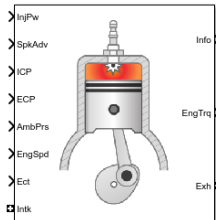
External Websites

Developing a Period-Based Air-Fuel Ratio Controller Using a Low-Cost Switching Sensor

SI Core Engine

Spark-ignition engine from intake to exhaust port

Library: Powertrain Blockset / Propulsion / Combustion Engine Components / Core Engine



Description

The SI Core Engine block implements a spark-ignition (SI) engine from intake to exhaust port. You can use the block in larger vehicle models, hardware-in-the-loop (HIL) engine control design, or vehicle-level fuel economy and performance simulations.

The SI Core Engine block calculates:

- Brake torque
- Fuel flow
- Port gas mass flow, including exhaust gas recirculation (EGR)
- Air-fuel ratio (AFR)
- Exhaust temperature and exhaust mass flow rate
- Engine-out (EO) exhaust emissions
 - Hydrocarbon (HC)
 - Carbon monoxide (CO)
 - Nitric oxide and nitrogen dioxide (NO_x)
 - Carbon dioxide (CO₂)
 - Particulate matter (PM)

Air Mass Flow

To calculate engine air mass flow, configure the SI engine to use either of these air mass flow models.

Air Mass Flow Model	Description
"SI Engine Speed-Density Air Mass Flow Model"	Uses the speed-density equation to calculate the engine air mass flow, relating the engine air mass flow to the intake manifold pressure and engine speed. Consider using this air mass flow model in engines with fixed valvetrain designs.

Air Mass Flow Model	Description
<p>“SI Engine Dual-Independent Cam Phaser Air Mass Flow Model”</p>	<p>To calculate the engine air mass flow, the dual-independent cam phaser model uses:</p> <ul style="list-style-type: none"> • Empirical calibration parameters developed from engine mapping measurements • Desktop calibration parameters derived from engine computer-aided design (CAD) data <p>In contrast to typical embedded air mass flow calculations based on direct air mass flow measurement with an air mass flow (MAF) sensor, this air mass flow model offers:</p> <ul style="list-style-type: none"> • Elimination of MAF sensors in dual cam-phased valvetrain applications • Reasonable accuracy with changes in altitude • Semiphysical modeling approach • Bounded behavior • Suitable execution time for electronic control unit (ECU) implementation • Systematic development of a relatively small number of calibration parameters

Brake Torque

To calculate the brake torque, configure the SI engine to use either of these torque models.

Brake Torque Model	Description
“SI Engine Torque Structure Model”	<p>For the structured brake torque calculation, the SI engine uses tables for the inner torque, friction torque, optimal spark, spark efficiency, and lambda efficiency.</p> <p>If you select Crank angle pressure and torque on the block Torque tab, you can:</p> <ul style="list-style-type: none"> • Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle. • Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals. • Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input. • Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque. • Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.
“SI Engine Simple Torque Model”	<p>For the simple brake torque calculation, the SI engine block uses a torque lookup table map that is a function of engine speed and load.</p>

Fuel Flow

To calculate the fuel flow, the SI Core Engine block uses fuel injector characteristics and fuel injector pulse-width.

$$\dot{m}_{fuel} = \frac{NS_{inj}Pw_{inj}N_{cyl}}{Cps\left(\frac{60s}{min}\right)\left(\frac{1000mg}{g}\right)}$$

To calculate the fuel economy for high-fidelity models, the block uses the volumetric fuel flow.

$$Q_{fuel} = \frac{\dot{m}_{fuel}}{\left(\frac{1000kg}{m^3}\right)Sg_{fuel}}$$

The equation uses these variables.

- \dot{m}_{fuel} Fuel mass flow, g/s
- ω Engine rotational speed, rad/s
- Cps Crankshaft revolutions per power stroke, rev/stroke
- S_{inj} Fuel injector slope, mg/ms
- Pw_{inj} Fuel injector pulse-width, ms

N_{cyl}	Number of engine cylinders
N	Engine speed, rpm
Sg_{fuel}	Specific gravity of fuel
Q_{fuel}	Volumetric fuel flow

The block uses the internal signal `FlwDir` to track the direction of the flow.

Air-Fuel Ratio

To calculate the air-fuel (AFR) ratio, the CI Core Engine and SI Core Engine blocks implement this equation.

$$AFR = \frac{\dot{m}_{air}}{\dot{m}_{fuel}}$$

The CI Core Engine uses this equation to calculate the relative AFR.

$$\lambda = \frac{AFR}{AFR_s}$$

To calculate the exhaust gas recirculation (EGR), the blocks implement this equation. The calculation expresses the EGR as a percent of the total intake port flow.

$$EGR_{pct} = 100 \frac{\dot{m}_{intk,b}}{\dot{m}_{intk}} = 100 y_{intk,b}$$

The equations use these variables.

AFR	Air-fuel ratio
AFR_s	Stoichiometric air-fuel ratio
\dot{m}_{intk}	Engine air mass flow
\dot{m}_{fuel}	Fuel mass flow
λ	Relative AFR
$y_{intk,b}$	Intake burned mass fraction
EGR_{pct}	EGR percent
$\dot{m}_{intk,b}$	Recirculated burned gas mass flow rate

Exhaust

The block calculates the:

- Exhaust gas temperature
- Exhaust gas-specific enthalpy
- Exhaust gas mass flow rate
- Engine-out (EO) exhaust emissions:
 - Hydrocarbon (HC)
 - Carbon monoxide (CO)

- Nitric oxide and nitrogen dioxide (NO_x)
- Carbon dioxide (CO₂)
- Particulate matter (PM)

The exhaust temperature determines the specific enthalpy.

$$h_{exh} = Cp_{exh}T_{exh}$$

The exhaust mass flow rate is the sum of the intake port air mass flow and the fuel mass flow.

$$\dot{m}_{exh} = \dot{m}_{intake} + \dot{m}_{fuel}$$

To calculate the exhaust emissions, the block multiplies the emission mass fraction by the exhaust mass flow rate. To determine the emission mass fractions, the block uses lookup tables that are functions of the engine torque and speed.

$$y_{exh,i} = f_{i_frac}(T_{brake}, N)$$

$$\dot{m}_{exh,i} = \dot{m}_{exh}y_{exh,i}$$

The fraction of air and fuel entering the intake port, injected fuel, and stoichiometric AFR determine the air mass fraction that exits the exhaust.

$$y_{exh,air} = \max\left[y_{in,air} - \frac{\dot{m}_{fuel} + y_{in,fuel}\dot{m}_{intake}}{\dot{m}_{fuel} + \dot{m}_{intake}}AFR_s\right]$$

If the engine is operating at the stoichiometric or fuel rich AFR, no air exits the exhaust. Unburned hydrocarbons and burned gas comprise the remainder of the exhaust gas. This equation determines the exhaust burned gas mass fraction.

$$y_{exh,b} = \max[(1 - y_{exh,air} - y_{exh,HC}), 0]$$

The equations use these variables.

T_{exh}	Engine exhaust temperature
h_{exh}	Exhaust manifold inlet-specific enthalpy
Cp_{exh}	Exhaust gas specific heat
\dot{m}_{intk}	Intake port air mass flow rate
\dot{m}_{fuel}	Fuel mass flow rate
\dot{m}_{exh}	Exhaust mass flow rate
$y_{in,fuel}$	Intake fuel mass fraction
$y_{exh,i}$	Exhaust mass fraction for $i = \text{CO}_2, \text{CO}, \text{HC}, \text{NO}_x, \text{air}, \text{burned gas}, \text{and PM}$
$\dot{m}_{exh,i}$	Exhaust mass flow rate for $i = \text{CO}_2, \text{CO}, \text{HC}, \text{NO}_x, \text{air}, \text{burned gas}, \text{and PM}$
T_{brake}	Engine brake torque
N	Engine speed
$y_{exh,air}$	Exhaust air mass fraction
$y_{exh,b}$	Exhaust air burned mass fraction

Power Accounting

For the power accounting, the block implements equations that depend on **Torque model**.

When you set **Torque model** to Simple Torque Lookup, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrIntkHeatFlw	Intake heat flow $\dot{m}_{intk}h_{intk}$
		PwrExheatFlw	Exhaust heat flow $-\dot{m}_{exh}h_{exh}$
		PwrCrkshft	Crankshaft power $-T_{brake}\omega$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrFuel	Fuel input power $\dot{m}_{fuel}LHV$
	PwrLoss	All losses $T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh}$	

Bus Signal		Description	Equations
	<p>PwrStored — Stored energy rate of change</p> <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	<i>Not used</i>	

When you set **Torque model** to Torque Structure, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	<p>PwrTrnsfrd — Power transferred between blocks</p> <ul style="list-style-type: none"> • Positive signals indicate flow into block • Negative signals indicate flow out of block 	PwrIntkHeatFlw	Intake heat flow $\dot{m}_{intk}h_{intk}$
		PwrExhHeatFlw	Exhaust heat flow $-\dot{m}_{exh}h_{exh}$
		PwrCrkshft	Crankshaft power $-T_{brake}\omega$
	<p>PwrNotTrnsfrd — Power crossing the block boundary, but not transferred</p> <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrFuel	Fuel input power $\dot{m}_{fuel}LHV$
		PwrFricLoss	Friction loss $-T_{fric}\omega$
		PwrPumpLoss	Pumping loss $-T_{pump}\omega$
		PwrHeatLoss	Heat transfer loss $T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh} + T_{fric}\omega + T_{pump}\omega$

Bus Signal		Description	Equations
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	<i>Not used</i>	

h_{exh}	Exhaust manifold inlet-specific enthalpy
h_{intk}	Intake port specific enthalpy
\dot{m}_{intk}	Intake port air mass flow rate
\dot{m}_{fuel}	Fuel mass flow rate
\dot{m}_{exh}	Exhaust mass flow rate
ω	Engine speed
T_{brake}	Brake torque
T_{pump}	Engine pumping work offset to inner torque
T_{fric}	Engine friction torque
LHV	Fuel lower heating value

Ports

Input

InjPw — Fuel injector pulse-width

scalar

Fuel injector pulse-width, Pw_{inj} , in ms.

SpkAdv — Spark advance

scalar

Spark advance, SA , in degrees crank angle before top dead center (degBTDC).

Dependencies

To create this port, for the **Torque model** parameter, select Torque Structure.

ICP — Intake cam phase angle command

scalar

Intake cam phase angle command, φ_{ICPCMD} , in degCrkAdv, or degrees crank advance.

Dependencies

To create this port, for the **Air mass flow model** parameter, select Dual-Independent Variable Cam Phasing.

ECP — Exhaust cam phase angle command

scalar

Exhaust cam phase angle command, φ_{ECPCMD} , in degCrkRet, or degrees crank retard.

Dependencies

To create this port, for the **Air mass flow model** parameter, select Dual-Independent Variable Cam Phasing.

AmbPrs — Ambient pressure

scalar

Ambient pressure, P_{Amb} , in Pa.

Dependencies

To create this port, for the **Air mass flow model** parameter, select Dual-Independent Variable Cam Phasing.

EngSpd — Engine speed

scalar

Engine speed, N , in rpm.

Ect — Engine cooling temperature

scalar

Engine cooling temperature, $T_{coolant}$, in K.

Dependencies

To enable this parameter, for **Torque model**, select Torque Structure.

Intk — Intake port pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the upstream:

- Prs — Pressure, in Pa
- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Intake port mass fractions, dimensionless. EGR mass flow at the intake port is burned gas.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen

- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Exh — Exhaust port pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the exhaust:

- Prs — Pressure, in Pa
- Temp — Temperature, in K
- Enth — Specific enthalpy, in J/kg
- MassFrac — Exhaust port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Output

Info — Bus signal

bus

Bus signal that contains these block calculations.

Signal	Description	Variable	Units
IntkGasMassFlw	Engine intake air mass flow	\dot{m}_{air}	kg/s
IntkAirMassFlw	Engine intake port mass flow	\dot{m}_{intk}	kg/s
NrmlzdAirChrg	Engine load (that is, normalized cylinder air mass) corrected for final steady-state cam phase angles	L	N/A
Afr	Air-fuel ratio at engine exhaust port	AFR	N/A
FuelMassFlw	Fuel flow into engine	\dot{m}_{fuel}	kg/s
FuelVolFlw	Volumetric fuel flow	Q_{fuel}	m ³ /s
ExhManGasTemp	Exhaust gas temperature at exhaust manifold inlet	T_{exh}	K
EngTrq	Engine brake torque	T_{brake}	N·m
EngSpd	Engine speed	N	rpm
IntkCamPhase	Intake cam phaser angle	φ_{ICP} i	degrees crank advance
ExhCamPhase	Exhaust cam phaser angle	φ_{ECP}	degrees crank retard
CrkAng	Engine crankshaft absolute angle	$\int_0^{(360)Cps} EngSpd \frac{180}{30} d\theta$ <p>where Cps is crankshaft revolutions per power stroke</p>	degrees crank angle
EgrPct	EGR percent	EGR_{pct}	N/A
EoAir	EO air mass flow rate	\dot{m}_{exh}	kg/s
EoBrndGas	EO burned gas mass flow rate	$y_{exh,b}$	kg/s
EoHC	EO hydrocarbon emission mass flow rate	$y_{exh,HC}$	kg/s
EoCO	EO carbon monoxide emission mass flow rate	$y_{exh,CO}$	kg/s
EoNOx	EO nitric oxide and nitrogen dioxide emissions mass flow rate	$y_{exh,NOx}$	kg/s
EoCO2	EO carbon dioxide emission mass flow rate	$y_{exh,CO2}$	kg/s

Signal		Description	Variable	Units	
EoPm		EO particulate matter emission mass flow rate	$y_{exh,PM}$	kg/s	
CylPrs		Cylinder pressure	N/A	Pa	
EngTrqCrk		Crank-angle based engine torque	N/A	N·m	
PwrInfo	PwrTrnsfrd	PwrIntkHeatFlw	Intake heat flow	$\dot{m}_{intk}h_{intk}$	W
		PwrExhHeatFlw	Exhaust heat flow	$-\dot{m}_{exh}h_{exh}$	W
		PwrCrkshft	Crankshaft power	$-T_{brake}\omega$	W
	PwrNotTrnsfrd	PwrFuel	Fuel input power	$\dot{m}_{fuel}LHV$	W
		PwrLoss	For Torque model set to Simple Torque Lookup: All losses	$T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh}$	W
		PwrFricLoss	For Torque model set to Torque Structure: Friction loss	$-T_{fric}\omega$	W
		PwrPumpLoss	For Torque model set to Torque Structure: Pumping loss	$-T_{pump}\omega$	W
		PwrHeatTrnsfrLoss	For Torque model set to Torque Structure: Heat transfer loss	$T_{brake}\omega - \dot{m}_{fuel}LHV - \dot{m}_{intk}h_{intk} + \dot{m}_{exh}h_{exh} + T_{fric}\omega + T_{pump}\omega$	W
	PwrStored	Not used			

EngTrq – Engine brake torque

scalar

Engine brake torque, T_{brake} , in N·m.

Intk – Intake port mass flow rate, heat flow rate, temperature, mass fraction

two-way connector port

Bus containing:

- MassFlwRate – Intake port mass flow rate, in kg/s
- HeatFlwRate – Intake port heat flow rate, in J/s
- Temp – Intake port temperature, in K
- MassFrac – Intake port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Exh — Exhaust port mass flow rate, heat flow rate, temperature, mass fraction
two-way connector port

Bus containing:

- MassFlwRate — Exhaust port mass flow rate, in kg/s
- HeatFlwRate — Exhaust heat flow rate, in J/s
- Temp — Exhaust temperature, in K
- MassFrac — Exhaust port mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Parameters

Block Options

Air mass flow model — Select air mass flow model

Dual-Independent Variable Cam Phasing (default) | Simple Speed-Density

To calculate engine air mass flow, configure the SI engine to use either of these air mass flow models.

Air Mass Flow Model	Description
"SI Engine Speed-Density Air Mass Flow Model"	Uses the speed-density equation to calculate the engine air mass flow, relating the engine air mass flow to the intake manifold pressure and engine speed. Consider using this air mass flow model in engines with fixed valvetrain designs.
"SI Engine Dual-Independent Cam Phaser Air Mass Flow Model"	<p>To calculate the engine air mass flow, the dual-independent cam phaser model uses:</p> <ul style="list-style-type: none"> • Empirical calibration parameters developed from engine mapping measurements • Desktop calibration parameters derived from engine computer-aided design (CAD) data <p>In contrast to typical embedded air mass flow calculations based on direct air mass flow measurement with an air mass flow (MAF) sensor, this air mass flow model offers:</p> <ul style="list-style-type: none"> • Elimination of MAF sensors in dual cam-phased valvetrain applications • Reasonable accuracy with changes in altitude • Semiphysical modeling approach • Bounded behavior • Suitable execution time for electronic control unit (ECU) implementation • Systematic development of a relatively small number of calibration parameters

Dependencies

The table summarizes the parameter dependencies.

Air Mass Flow Model	Enables Parameters
Dual-Independent Variable Cam Phasing	<p>Cylinder volume at intake valve close table, f_vivc</p> <p>Cylinder volume intake cam phase breakpoints, f_vivc_icp_bpt</p> <p>Cylinder trapped mass correction factor, f_tm_corr</p> <p>Normalized density breakpoints, f_tm_corr_nd_bpt</p> <p>Engine speed breakpoints, f_tm_corr_n_bpt</p> <p>Air mass flow, f_mdot_air</p> <p>Exhaust cam phase breakpoints, f_mdot_air_ecp_bpt</p> <p>Trapped mass flow breakpoints, f_mdot_trpd_bpt</p> <p>Air mass flow correction factor, f_mdot_air_corr</p> <p>Engine load breakpoints for air mass flow correction, f_mdot_air_corr_ld_bpt</p> <p>Engine speed breakpoints for air mass flow correction, f_mdot_air_n_bpt</p>
Simple Speed Density	<p>Speed-density volumetric efficiency, f_nv</p> <p>Speed-density intake manifold pressure breakpoints, f_nv_prs_bpt</p> <p>Speed-density engine speed breakpoints, f_nv_n_bpt</p>

Torque model – Select torque model

Torque Structure (default) | Simple Torque Lookup

To calculate the brake torque, configure the SI engine to use either of these torque models.

Brake Torque Model	Description
"SI Engine Torque Structure Model"	<p>For the structured brake torque calculation, the SI engine uses tables for the inner torque, friction torque, optimal spark, spark efficiency, and lambda efficiency.</p> <p>If you select Crank angle pressure and torque on the block Torque tab, you can:</p> <ul style="list-style-type: none"> • Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle. • Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals. • Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input. • Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque. • Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.
"SI Engine Simple Torque Model"	<p>For the simple brake torque calculation, the SI engine block uses a torque lookup table map that is a function of engine speed and load.</p>

Dependencies

The table summarizes the parameter dependencies.

Torque Model	Enables Parameters
Torque Structure	<p>Inner torque table, f_tq_inr</p> <p>Friction torque table, f_tq_fric</p> <p>Engine temperature modifier on friction torque, f_fric_temp_mod</p> <p>Engine temperature modifier breakpoints, f_fric_temp_bpt</p> <p>Pumping work table, f_tq_pump</p> <p>Optimal spark table, f_sa_opt</p> <p>Inner torque load breakpoints, f_tq_inr_l_bpt</p> <p>Inner torque speed breakpoints, f_tq_inr_n_bpt</p> <p>Spark efficiency table, f_m_sa</p> <p>Spark retard from optimal, f_del_sa_bpt</p> <p>Lambda efficiency, f_m_lam</p> <p>Lambda breakpoints, f_m_lam_bpt</p>
Simple Torque Lookup	<p>Torque table, f_tq_nl</p> <p>Torque table load breakpoints, f_tq_nl_l_bpt</p> <p>Torque table speed breakpoints, f_tq_nl_n_bpt</p>

Air

Number of cylinders, NCyl – Engine cylinders

4 (default) | scalar

Number of engine cylinders, N_{cyl} .

Crank revolutions per power stroke, Cps – Revolutions per stroke

2 (default) | scalar

Crankshaft revolutions per power stroke, Cps , in rev/stroke.

Total displaced volume, Vd – Volume

0.0015 (default) | scalar

Displaced volume, V_d , in m^3 .

Ideal gas constant air, Rair – Constant

287 (default) | scalar

Ideal gas constant, R_{air} , in $J/(kg \cdot K)$.

Air standard pressure, Pstd – Pressure

101325 (default) | scalar

Standard air pressure, P_{std} , in Pa.

Air standard temperature, T_{std} – Temperature

293.15 (default) | scalar

Standard air temperature, T_{std} , in K.

Speed-density volumetric efficiency, f_{η_v} – Lookup table

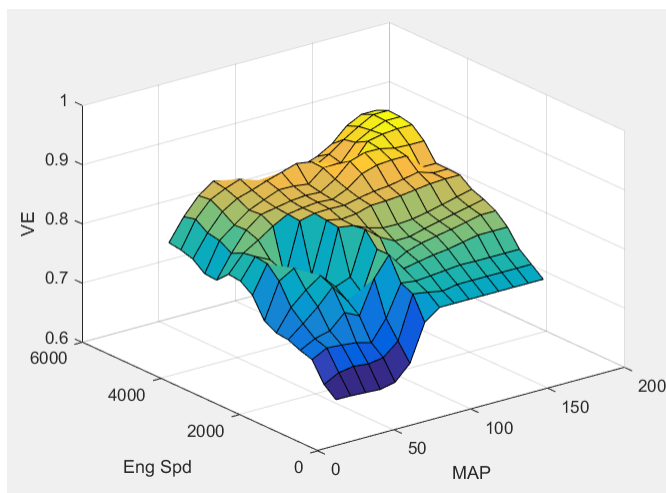
array

The engine volumetric efficiency lookup table, f_{η_v} , is a function of intake manifold absolute pressure and engine speed

$$\eta_v = f_{\eta_v}(MAP, N)$$

where:

- η_v is engine volumetric efficiency, dimensionless.
- MAP is intake manifold absolute pressure, in KPa.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Simple Speed-Density.

Speed-density intake manifold pressure breakpoints, $f_{\eta_v_prs_bpt}$ – Breakpoints

[31 40.6428571428571 50.2857142857143 59.9285714285714 69.5714285714286
79.2142857142857 88.8571428571429 98.5 108.142857142857 117.785714285714
127.428571428571 137.071428571429 146.714285714286 156.357142857143 166]
(default) | array

Intake manifold pressure breakpoints for speed-density volumetric efficiency lookup table, in KPa.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Simple Speed-Density.

Speed-density engine speed breakpoints, $f_{nv_n_bpt}$ — Breakpoints

[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default) | array

Engine speed breakpoints for speed-density volumetric efficiency lookup table, in rpm.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Simple Speed-Density.

Cylinder volume at intake valve close table, f_{vivc} — 2-D lookup table

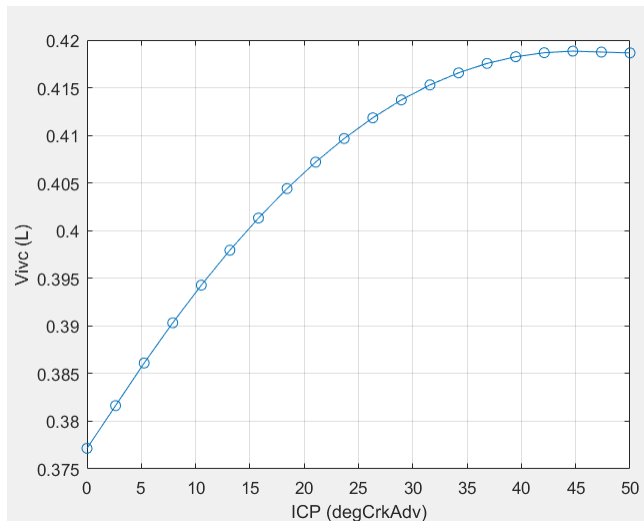
array

The cylinder volume at intake valve close table (IVC), f_{vivc} is a function of the intake cam phaser angle

$$V_{IVC} = f_{vivc}(\varphi_{ICP})$$

where:

- V_{IVC} is cylinder volume at IVC, in L.
- φ_{ICP} is intake cam phaser angle, in crank advance degrees.



Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Cylinder volume intake cam phase breakpoints, $f_{vivc_icp_bpt}$ — Breakpoints

[0 2.6316 5.2632 7.8947 10.5263 13.1579 15.7895 18.4211 21.0526 23.6842 26.3158 28.9474 31.5789 34.2105 36.8421 39.4737 42.1053 44.7368 47.3684 50] (default) | vector

Cylinder volume intake cam phase breakpoints, in L.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Cylinder trapped mass correction factor, $f_{TM_{corr}}$ — Lookup table

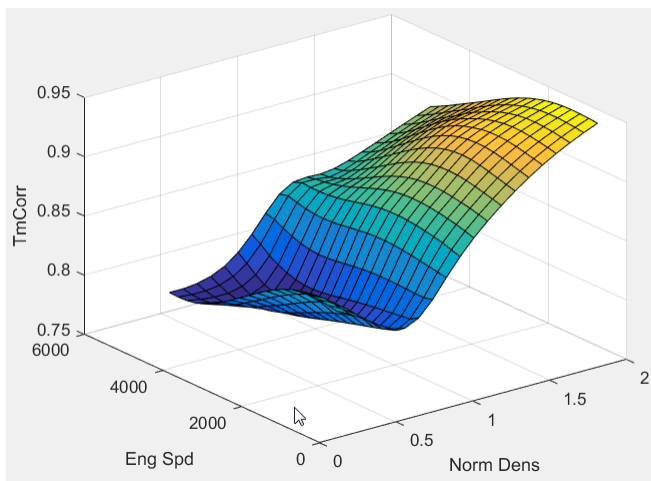
array

The trapped mass correction factor table, $f_{TM_{corr}}$, is a function of the normalized density and engine speed

$$TM_{corr} = f_{TM_{corr}}(\rho_{norm}, N)$$

where:

- TM_{corr} , is trapped mass correction multiplier, dimensionless.
- ρ_{norm} is normalized density, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Normalized density breakpoints, $f_{tm_corr_nd_bpt}$ — Breakpoints

[0.3 0.38947 0.47895 0.56842 0.65789 0.74737 0.83684 0.92632 1.0158 1.1053 1.1947 1.2842 1.3737 1.4632 1.5526 1.6421 1.7316 1.8211 1.9105 2] (default) | vector

Normalized density breakpoints, dimensionless.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Engine speed breakpoints, $f_{tm_corr_n_bpt}$ — Breakpoints

[750 973.6842 1197.3684 1421.0526 1644.7368 1868.4211 2092.1053 2315.7895 2539.4737 2763.1579 2986.8421 3210.5263 3434.2105 3657.8947 3881.5789 4105.2632 4328.9474 4552.6316 4776.3158 5000] (default) | vector

Engine speed breakpoints, in rpm.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Intake mass flow, f_{mdot_intk} — Lookup table

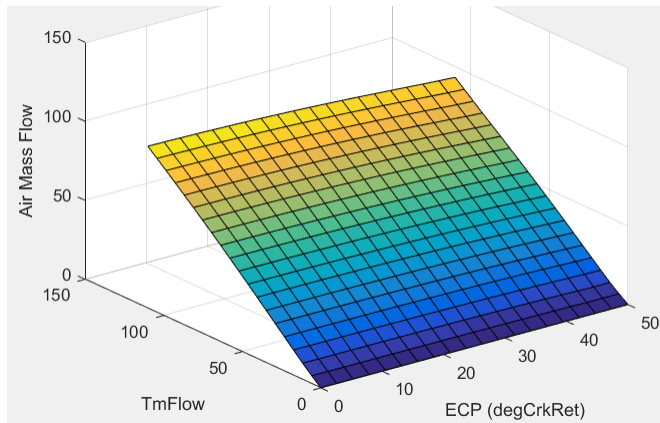
array

The phaser intake mass flow model lookup table is a function of exhaust cam phaser angles and trapped air mass flow

$$\dot{m}_{intkideal} = f_{intkideal}(\varphi_{ECP}, TM_{flow})$$

where:

- $\dot{m}_{intkideal}$ is engine intake port mass flow at arbitrary cam phaser angles, in g/s.
- φ_{ECP} is exhaust cam phaser angle, in degrees crank retard.
- TM_{flow} is flow rate equivalent to corrected trapped mass at the current engine speed, in g/s.



Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Exhaust cam phase breakpoints, $f_{mdot_air_ecp_bpt}$ — Breakpoints

[0 2.6316 5.2632 7.8947 10.5263 13.1579 15.7895 18.4211 21.0526 23.6842 26.3158 28.9474 31.5789 34.2105 36.8421 39.4737 42.1053 44.7368 47.3684 50] (default) | vector

Exhaust cam phaser breakpoints for air mass flow lookup table, in degrees crank retard.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Trapped mass flow breakpoints, $f_mdot_trpd_bpt$ – Breakpoints

[0 5.7895 11.5789 17.3684 23.1579 28.9474 34.7368 40.5263 46.3158 52.1053 57.8947 63.6842 69.4737 75.2632 81.0526 86.8421 92.6316 98.4211 104.2105 110]
(default) | vector

Trapped mass flow breakpoints for air mass flow lookup table, in g/s.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Air mass flow correction factor, $f_mdot_air_corr$ – Lookup table

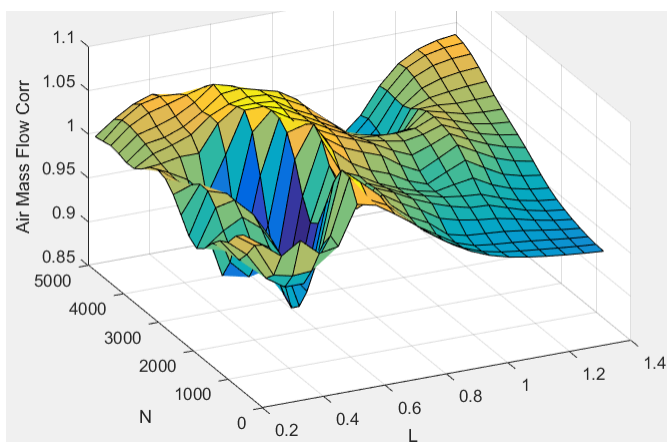
array

The intake air mass flow correction lookup table, $f_{aircorr}$, is a function of ideal load and engine speed

$$\dot{m}_{air} = \dot{m}_{intkideal} f_{aircorr}(L_{ideal}, N)$$

where:

- L_{ideal} is engine load (normalized cylinder air mass) at arbitrary cam phaser angles, uncorrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.
- \dot{m}_{air} is engine intake air mass flow final correction at steady-state cam phaser angles, in g/s.
- $\dot{m}_{intkideal}$ is engine intake port mass flow at arbitrary cam phaser angles, in g/s.



Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Engine load breakpoints for air mass flow correction, $f_{\text{mdot_air_corr_ld_bpt}}$ – Breakpoints

vector

Engine load breakpoints for air mass flow final correction, dimensionless.

Dependencies

To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Engine speed breakpoints for air mass flow correction, $f_{\text{mdot_air_n_bpt}}$ – Breakpoints

vector

Engine speed breakpoints for air mass flow final correction, in rpm.

Dependencies

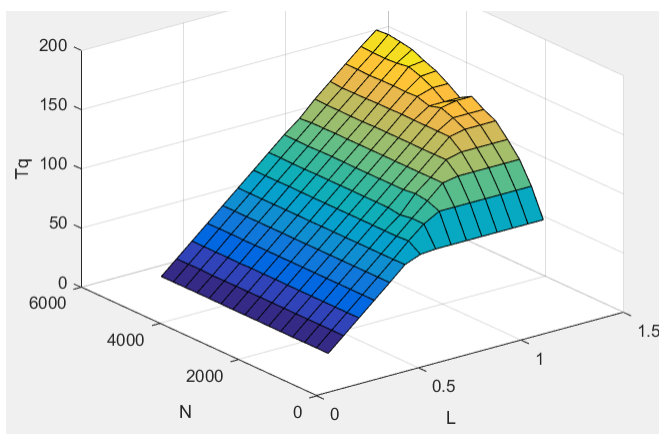
To enable this parameter, for the **Air mass flow model** parameter, select Dual - Independent Variable Cam Phasing.

Torque**Torque table, $f_{\text{tq_nl}}$ – Lookup table**

[L x N] array

For the simple torque lookup table model, the SI engine uses a lookup table map that is a function of engine speed and load, $T_{\text{brake}} = f_{TnL}(L, N)$, where:

- T_{brake} is engine brake torque after accounting for spark advance, AFR, and friction effects, in N·m.
- L is engine load, as a normalized cylinder air mass, dimensionless.
- N is engine speed, in rpm.



The simple torque lookup model assumes that the calibration has negative torque values to indicate the non-firing engine load (L) versus speed (N) condition. The calibrated table (L -by- N) contains the non-firing data in the first table row (1-by- N). When the fuel delivered to the engine is zero, the model uses the data in the first table row (1-by- N) at or above 100 AFR. 100 AFR results from fuel cutoff or very lean operation where combustion cannot occur.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Torque table load breakpoints, $f_{tq_nl_l_bpt}$ — Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector | [1 x L] vector

Engine load breakpoints, L , dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Torque table speed breakpoints, $f_{tq_nl_n_bpt}$ — Breakpoints

[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default) | vector | [1 x N] vector

Engine speed breakpoints, N , in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Simple Torque Lookup.

Crank angle pressure and torque — Enable Crank angle signals

off (default) | on

If you select **Crank angle pressure and torque** on the block **Torque** tab, you can:

- Simulate advanced closed-loop engine controls in desktop simulations and on HIL bench, based on cylinder pressure recorded from a model or laboratory test as a function of crank angle.
- Simulate driveline vibrations downstream of the engine due to high-frequency crankshaft torsionals.
- Simulate engine misfires due to lean operation or spark plug fouling by using the injector pulse width input.
- Simulate cylinder deactivation effect (closed intake and exhaust valves, no injected fuel) on individual cylinder pressures, mean-value airflow, mean-value torque, and crank-angle-based torque.
- Simulate the fuel-cut effect on individual cylinder pressure, mean-value torque, and crank-angle-based torque.

Dependencies

To enable this parameter, set **Torque model** to Torque Structure.

Cylinder pressure, f_{crk_prs} — Cylinder pressure table

$L \times M \times N$ array

Cylinder pressure table Prs , as a function of speed N , load L , and crank angle M , in Pa.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Brake torque, f_crk_btq — Brake torque table

$L \times M \times N$ array

Brake torque table T_{brake} , as a function of speed N , load L , and crank angle M , in N·m.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Speed breakpoints, f_crk_n_bpt — Speed breakpoints

[750 5000] (default) | $1 \times N$ vector

Speed breakpoints, N , in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Load breakpoints, f_crk_l_bpt — Load breakpoints

[0.2 1.4] (default) | $1 \times L$ vector

Load breakpoints, L . No dimension.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Crank angle breakpoints, f_crk_ang_bpt — Crank angle breakpoints

[60 660] (default) | $1 \times M$ vector

Crank angle breakpoints, M , in deg.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

TDC compression angles by cylinder, f_crk_tdc_ang — TDC compression angles by cylinder

[0 540 180 360] (default) | vector

Top dead center (TDC) compression angles by cylinder, in deg.

Dependencies

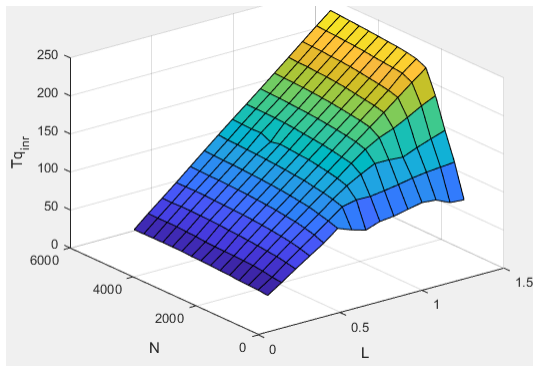
To enable this parameter, for the **Torque model** parameter, select Torque Structure. Select **Crank angle pressure and torque**.

Inner torque table, f_tq_inr — Lookup table

array

The inner torque lookup table, $f_{Tq_{inr}}$, is a function of engine speed and engine load, $T_{q_{inr}} = f_{Tq_{inr}}(L, N)$, where:

- $T_{q_{inr}}$ is inner torque based on gross indicated mean effective pressure, in N·m.
- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.



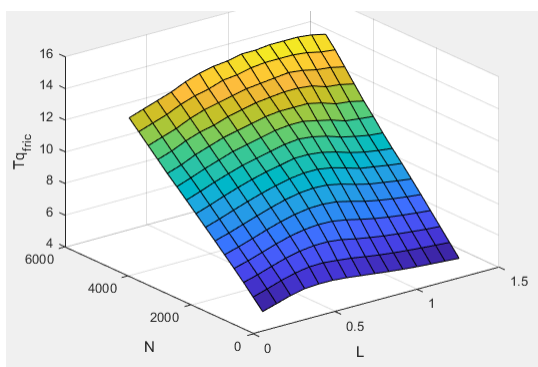
Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Friction torque table, $f_{T_{fric}}$ — Lookup table array

The friction torque lookup table, $f_{T_{fric}}$, is a function of engine speed and engine load, $T_{fric} = f_{T_{fric}}(L, N)$, where:

- T_{fric} is friction torque offset to inner torque, in N·m.
- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Engine temperature modifier on friction torque, $f_{fric_temp_mod}$ — Lookup table

```
[3.96 3.22 2.56 2.26 2.11 2 1.9 1.83 1.76 1.7 1.65 1.6 1.55 1.49 1.44 1.41
1.38 1.35 1.32 1.3 1.27 1.25 1.24 1.21 1.2 1.18 1.16 1.15 1.13 1.12 1.11 1.1
```

1.09 1.08 1.07 1.06 1.05 1.05 1.04 1.03 1.02 1.02 1.01 1.01 1 1 1 0.999 0.997
0.995 0.993 0.991 0.989 0.987] (default) | vector | vector

Engine temperature modifier on friction torque, $f_{fric,temp}$, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Engine temperature modifier breakpoints, f_fric_temp_bpt – Breakpoints

[274 276 278 280 282 284 286 288 290 292 294 296 298 300 302 304 306 308 310
312 314 316 318 320 322 324 326 328 330 332 334 336 338 340 342 344 346 348
350 352 354 356 358 360 362 364 366 368 370 372 374 376 378 380] (default) |
vector | vector

Engine temperature modifier breakpoints, in K.

Dependencies

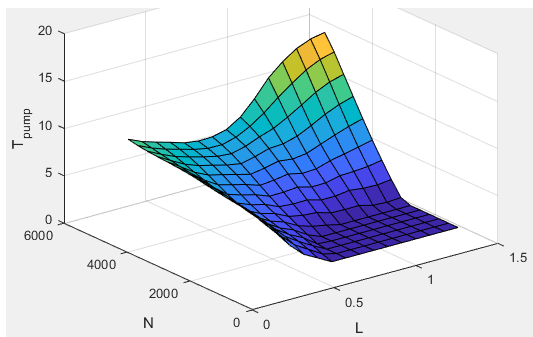
To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Pumping work table, f_tq_pump – Lookup table

array

The pumping work lookup table, $f_{T_{pump}}$, is a function of engine load and engine speed,
 $T_{pump} = f_{T_{pump}}(L, N)$, where:

- T_{pump} is pumping work, in N·m.
- L is engine load, as a normalized cylinder air mass, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

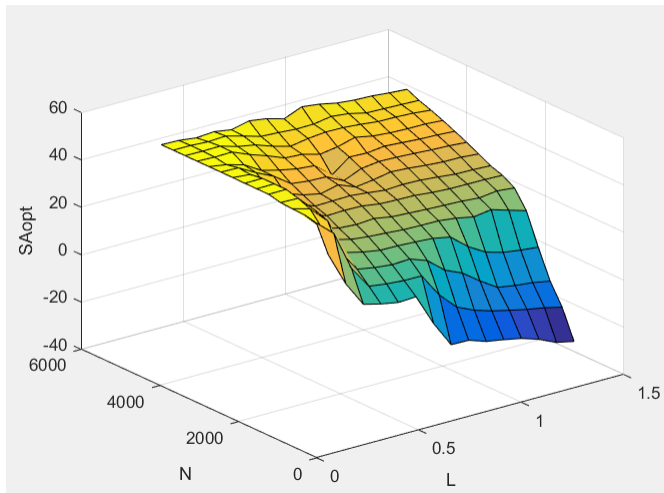
Optimal spark table, f_sa_opt – Lookup table

array

The optimal spark lookup table, $f_{SA_{opt}}$, is a function of engine speed and engine load,
 $SA_{opt} = f_{SA_{opt}}(L, N)$, where:

- SA_{opt} is optimal spark advance timing for maximum inner torque at stoichiometric air-fuel ratio (AFR), in deg.

- L is engine load at arbitrary cam phaser angles, corrected for final steady-state cam phaser angles, dimensionless.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Inner torque load breakpoints, $f_{tq_inr_l_bpt}$ — Breakpoints

[0.2 0.28571 0.37143 0.45714 0.54286 0.62857 0.71429 0.8 0.88571 0.97143 1.0571 1.1429 1.2286 1.3143 1.4] (default) | vector

Inner torque load breakpoints, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Inner torque speed breakpoints, $f_{tq_inr_n_bpt}$ — Breakpoints

[750 1053.5714 1357.1429 1660.7143 1964.2857 2267.8571 2571.4286 2875 3178.5714 3482.1429 3785.7143 4089.2857 4392.8571 4696.4286 5000] (default) | vector

Inner torque speed breakpoints, in rpm.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Spark efficiency table, f_{m_sa} — Lookup table

array

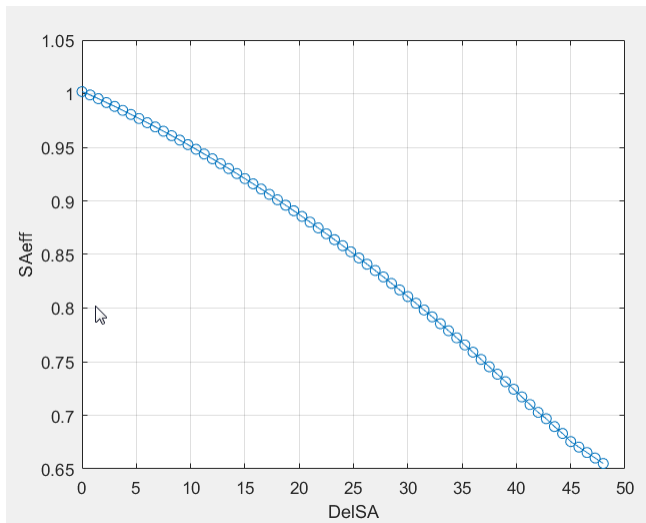
The spark efficiency lookup table, f_{Msa} , is a function of the spark retard from optimal

$$M_{sa} = f_{Msa}(\Delta SA)$$

$$\Delta SA = SA_{opt} - SA$$

where:

- M_{sa} is the spark retard efficiency multiplier, dimensionless.
- ΔSA is the spark retard timing distance from optimal spark advance, in deg.



Dependencies

To enable this parameter, for the **Torque model** parameter, select **Torque Structure**.

Spark retard from optimal, f_del_sa_bpt — Breakpoints

```
[0 0.75 1.5 2.25 3 3.75 4.5 5.25 6 6.75 7.5 8.25 9 9.75 10.5 11.25 12 12.75
13.5 14.25 15 15.75 16.5 17.25 18 18.75 19.5 20.25 21 21.75 22.5 23.25 24
24.75 25.5 26.25 27 27.75 28.5 29.25 30 30.75 31.5 32.25 33 33.75 34.5 35.25
36 36.75 37.5 38.25 39 39.75 40.5 41.25 42 42.75 43.5 44.25 45 45.75 46.5
47.25 48] (default) | vector
```

Spark retard from optimal inner torque timing breakpoints, in deg.

Dependencies

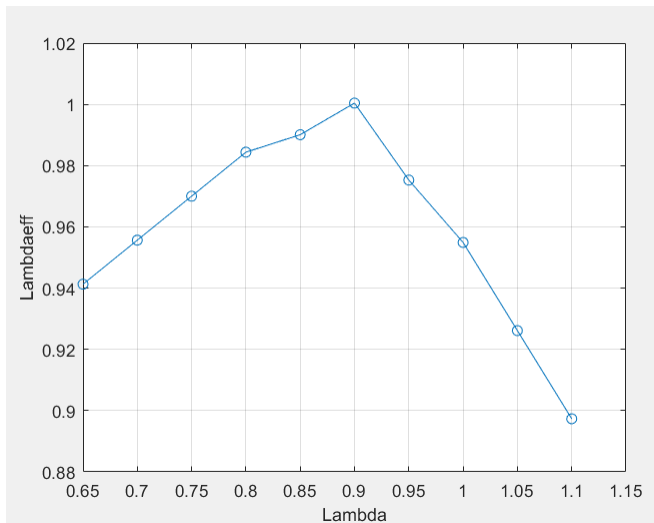
To enable this parameter, for the **Torque model** parameter, select **Torque Structure**.

Lambda efficiency, f_m_lam — Lookup table

array

The lambda efficiency lookup table, $f_{M\lambda}$, is a function of lambda, $M_\lambda = f_{M\lambda}(\lambda)$, where:

- M_λ is the lambda multiplier on inner torque to account for the air-fuel ratio (AFR) effect, dimensionless.
- λ is lambda, AFR normalized to stoichiometric fuel AFR, dimensionless.



Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Lambda breakpoints, `f_m_lam_bpt` – Breakpoints

[0.65 0.7 0.75 0.8 0.85 0.9 0.95 1 1.05 1.1] (default) | vector

Lambda effect on inner torque lambda breakpoints, dimensionless.

Dependencies

To enable this parameter, for the **Torque model** parameter, select Torque Structure.

Exhaust

Exhaust temperature table, `f_t_exh` – Lookup table

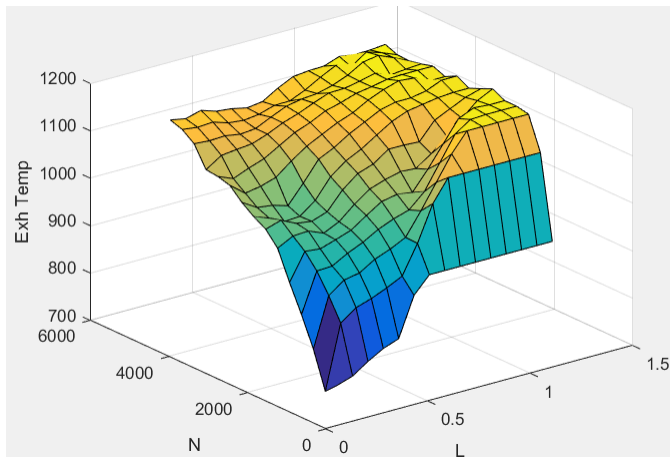
array

The exhaust temperature lookup table, f_{Texh} , is a function of engine load and engine speed

$$T_{exh} = f_{Texh}(L, N)$$

where:

- T_{exh} is engine exhaust temperature, in K.
- L is normalized cylinder air mass or engine load, dimensionless.
- N is engine speed, in rpm.



Load breakpoints, $f_t_exh_l_bpt$ – Breakpoints

[0.2 0.275 0.35 0.425 0.5 0.575 0.65 0.725 0.8 0.875 0.95 1.025 1.1 1.175 1.25] (default) | vector

Engine load breakpoints used for exhaust temperature lookup table, dimensionless.

Speed breakpoints, $f_t_exh_n_bpt$ – Breakpoints

[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default) | vector

Engine speed breakpoints used for exhaust temperature lookup table, in rpm.

Exhaust gas specific heat at constant pressure, cp_exh – Specific heat

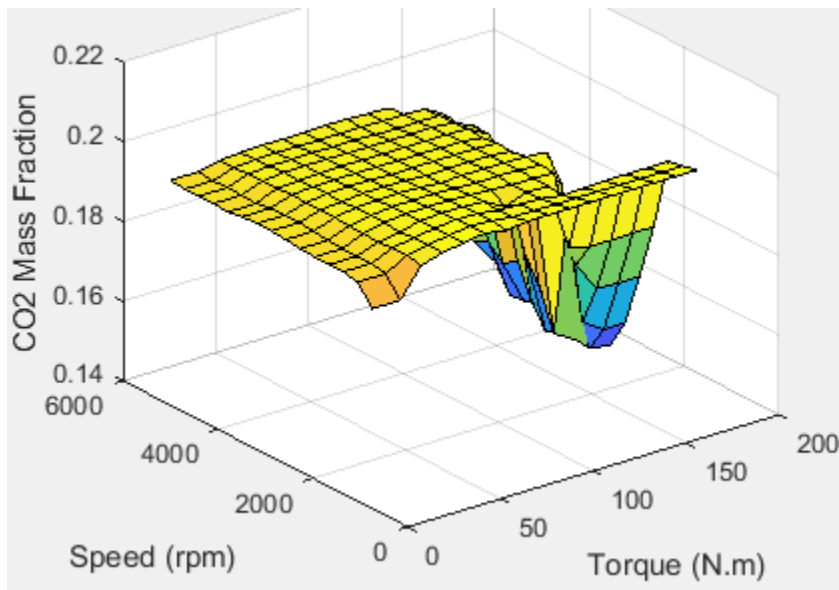
1005 (default) | scalar

Exhaust gas-specific heat, Cp_{exh} , in J/(kg·K).

CO₂ mass fraction table, f_CO2_frac – Carbon dioxide (CO₂) emission lookup table
array

The SI Core Engine CO₂ emission mass fraction lookup table is a function of engine torque and engine speed, $CO_2\ Mass\ Fraction = f(Speed, Torque)$, where:

- *CO₂ Mass Fraction* is the CO₂ emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



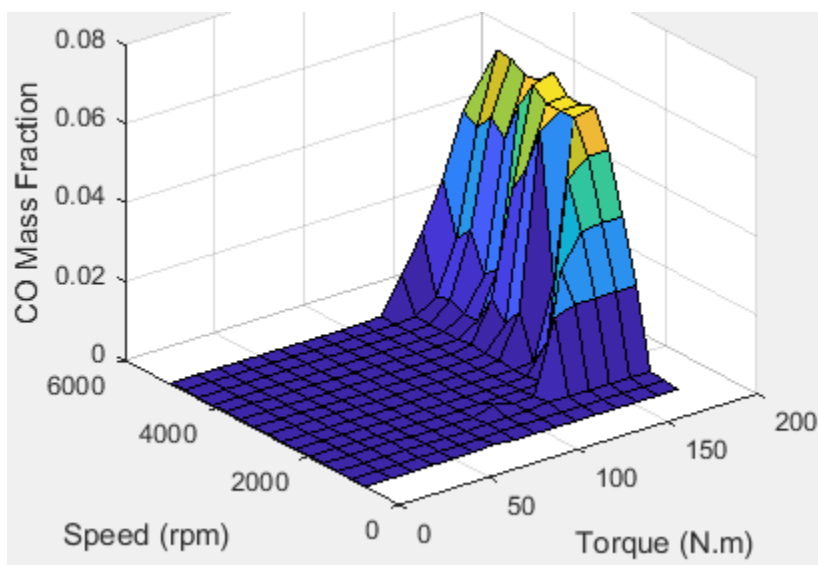
Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO2**.

CO mass fraction table, `f_CO_frac` – Carbon monoxide (CO) emission lookup table array

The SI Core Engine CO emission mass fraction lookup table is a function of engine torque and engine speed, $CO\ Mass\ Fraction = f(Speed, Torque)$, where:

- *CO Mass Fraction* is the CO emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



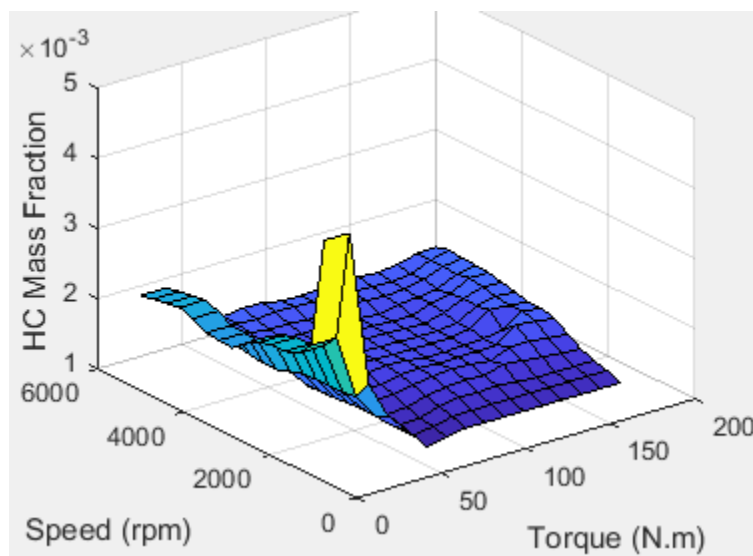
Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO**.

HC mass fraction table, f_{HC_frac} – Hydrocarbon (HC) emission lookup table array

The SI Core Engine HC emission mass fraction lookup table is a function of engine torque and engine speed, $HC\ Mass\ Fraction = f(Speed, Torque)$, where:

- *HC Mass Fraction* is the HC emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



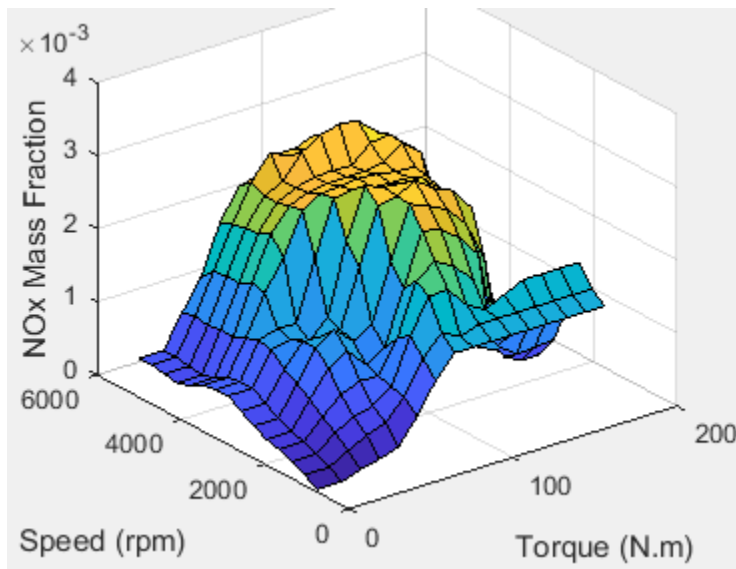
Dependencies

To enable this parameter, on the **Exhaust** tab, select **HC**.

NOx mass fraction table, f_{NOx_frac} – Nitric oxide and nitrogen dioxide (NOx) emission lookup table array

The SI Core Engine NOx emission mass fraction lookup table is a function of engine torque and engine speed, $NOx\ Mass\ Fraction = f(Speed, Torque)$, where:

- *NOx Mass Fraction* is the NOx emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.



Dependencies

To enable this parameter, on the **Exhaust** tab, select **NOx**.

PM mass fraction table, `f_PM_frac` – Particulate matter (PM) emission lookup table array

The SI Core Engine PM emission mass fraction lookup table is a function of engine torque and engine speed where:

- *PM* is the PM emission mass fraction, dimensionless.
- *Speed* is engine speed, in rpm.
- *Torque* is engine torque, in N·m.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **PM**.

Engine speed breakpoints, `f_exhfrac_n_bpt` – Breakpoints

```
[750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571
2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286
3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000]
(default) | vector
```

Engine speed breakpoints used for the emission mass fractions lookup tables, in rpm.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO2**, **CO**, **NOx**, **HC**, or **PM**.

Engine torque breakpoints, `f_exhfrac_trq_bpt` – Breakpoints

```
[0 15 26.4285714285714 37.8571428571429 49.2857142857143 60.7142857142857
72.1428571428571 83.5714285714286 95 106.428571428571 117.857142857143
129.285714285714 140.714285714286 152.142857142857 163.571428571429 175]
(default) | vector
```

Engine torque breakpoints used for the emission mass fractions lookup tables, in N·m.

Dependencies

To enable this parameter, on the **Exhaust** tab, select **CO₂**, **CO**, **NO_x**, **HC**, or **PM**.

Fuel**Injector slope, S_{inj} – Slope**

6.45161290322581 (default) | scalar

Fuel injector slope, S_{inj} , mg/ms.

Stoichiometric air-fuel ratio, afr_{stoich} – Air-fuel ratio

14.6 (default) | scalar

Air-fuel ratio, AFR .

Fuel lower heating value, $fuel_lhv$ – Heating value

46e6 (default) | scalar

Fuel lower heating value, LHV , in J/kg.

Fuel specific gravity, $fuel_sg$ – Specific gravity

0.745 (default) | scalar

Specific gravity of fuel, Sg_{fuel} , dimensionless.

Version History

Introduced in R2017a

References

- [1] Gerhardt, J., Hönninger, H., and Bischof, H., *A New Approach to Functional and Software Structure for Engine Management Systems – BOSCH ME7*. SAE Technical Paper 980801, 1998.
- [2] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

SI Controller | Mapped SI Engine

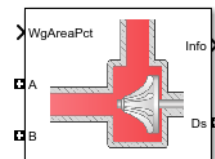
Topics

“SI Core Engine Air Mass Flow and Torque Production”
“Engine Calibration Maps”

Turbine

Turbine for boosted engines

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Boost

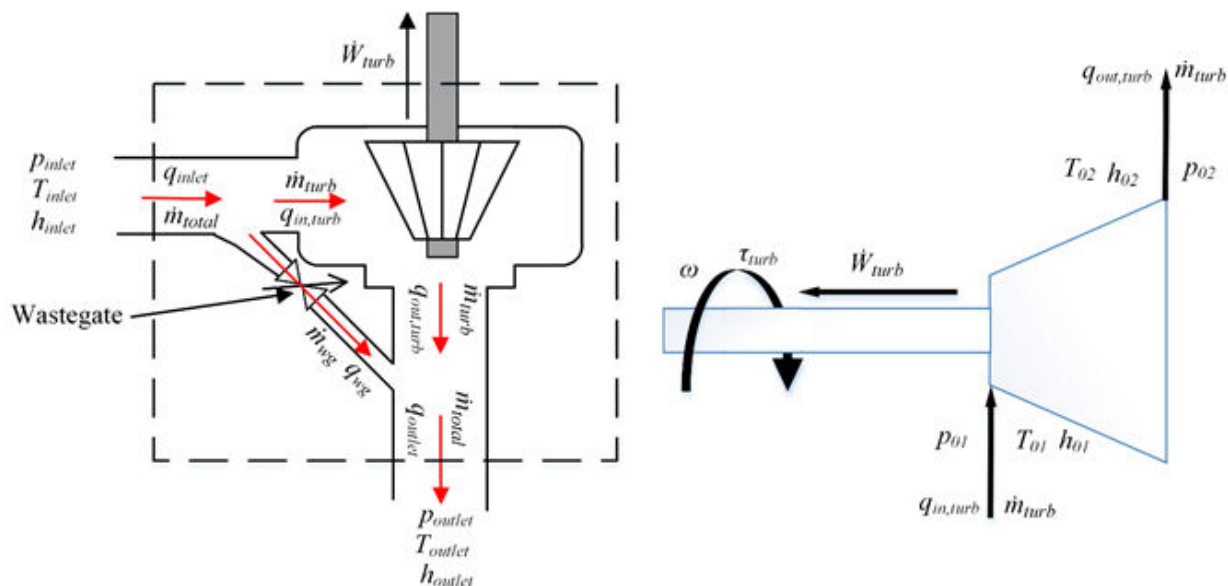


Description

The Turbine block uses the conservation of mass and energy to calculate mass and heat flow rates for turbines with either fixed or variable geometry. You can configure the block with a wastegate valve to bypass the turbine. The block uses two-way ports to connect to the inlet and outlet control volumes and the drive shaft. You can specify the lookup tables to calculate the mass flow rate and turbine efficiency. Typically, turbine manufacturers provide the mass flow rate and efficiency tables as a function of corrected speed and pressure ratio. The block does not support reverse mass flow.

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the mass flow rate and turbine efficiency lookup tables using measured data.

The mass flows from the inlet control volume to outlet control volume.



The Turbine block implements equations to model the performance, wastegate flow, and combined flow.

Virtual Calibration

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the corrected mass flow rate and turbine efficiency lookup tables using measured data. The dialog box steps through these tasks.

Task	Description																																																	
Import turbine data	Import this turbine data from a file. For more information, see “Using Data” (Model-Based Calibration Toolbox).																																																	
	<table border="1" data-bbox="505 386 1474 1734"> <thead> <tr> <th data-bbox="505 386 756 428">Turbine type</th> <th data-bbox="761 386 1474 428">Data</th> </tr> </thead> <tbody> <tr> <td data-bbox="505 434 756 1016">Fixed geometry</td> <td data-bbox="761 434 1474 1016"> <ul style="list-style-type: none"> • Speed, Spd, in rad/s • Corrected mass flow rate, MassFlwRate, in kg/s • Pressure ratio, PrsRatio, dimensionless • Efficiency, Eff, dimensionless <p>The speed, corrected mass flow rate, pressure ratio, and efficiency are in the 2nd-5th columns of the data file, respectively. The first and second rows of the data file provide the variable names and units. For example, use this format.</p> <table border="1" data-bbox="764 806 1471 1012"> <tr> <td>Name:</td> <td>Spd</td> <td>MassFlwRate</td> <td>PrsRatio</td> <td>Eff</td> </tr> <tr> <td>Unit:</td> <td>rad/s</td> <td>kg/s</td> <td></td> <td></td> </tr> <tr> <td>Data:</td> <td>8373.3</td> <td>0.02</td> <td>1.21</td> <td>0.44</td> </tr> <tr> <td></td> <td>...</td> <td>...</td> <td>...</td> <td>...</td> </tr> </table> </td> </tr> <tr> <td data-bbox="505 1022 756 1734">Variable geometry</td> <td data-bbox="761 1022 1474 1734"> <ul style="list-style-type: none"> • Speed, Spd, in rad/s • Corrected mass flow rate, MassFlwRate, kg/s • Rack position, RackPos, dimensionless • Pressure ratio, PrsRatio, dimensionless • Efficiency, Eff, dimensionless <p>Include data for several test points at each rack position operating point.</p> <p>The speed, corrected mass flow rate, rack position, pressure ratio, and efficiency are in the 2nd-6th columns of the data file, respectively. The first and second rows of the data file provide the variable names and units. For example, use this format.</p> <table border="1" data-bbox="764 1524 1471 1730"> <tr> <td>Name:</td> <td>Spd</td> <td>MassFlwRate</td> <td>RackPos</td> <td>PrsRatio</td> <td>Eff</td> </tr> <tr> <td>Unit:</td> <td>rad/s</td> <td>kg/s</td> <td></td> <td></td> <td></td> </tr> <tr> <td>Data:</td> <td>8373.3</td> <td>0.02</td> <td>1</td> <td>1.21</td> <td>0.44</td> </tr> <tr> <td></td> <td>...</td> <td>...</td> <td></td> <td>...</td> <td>...</td> </tr> </table> </td> </tr> </tbody> </table>	Turbine type	Data	Fixed geometry	<ul style="list-style-type: none"> • Speed, Spd, in rad/s • Corrected mass flow rate, MassFlwRate, in kg/s • Pressure ratio, PrsRatio, dimensionless • Efficiency, Eff, dimensionless <p>The speed, corrected mass flow rate, pressure ratio, and efficiency are in the 2nd-5th columns of the data file, respectively. The first and second rows of the data file provide the variable names and units. For example, use this format.</p> <table border="1" data-bbox="764 806 1471 1012"> <tr> <td>Name:</td> <td>Spd</td> <td>MassFlwRate</td> <td>PrsRatio</td> <td>Eff</td> </tr> <tr> <td>Unit:</td> <td>rad/s</td> <td>kg/s</td> <td></td> <td></td> </tr> <tr> <td>Data:</td> <td>8373.3</td> <td>0.02</td> <td>1.21</td> <td>0.44</td> </tr> <tr> <td></td> <td>...</td> <td>...</td> <td>...</td> <td>...</td> </tr> </table>	Name:	Spd	MassFlwRate	PrsRatio	Eff	Unit:	rad/s	kg/s			Data:	8373.3	0.02	1.21	0.44		Variable geometry	<ul style="list-style-type: none"> • Speed, Spd, in rad/s • Corrected mass flow rate, MassFlwRate, kg/s • Rack position, RackPos, dimensionless • Pressure ratio, PrsRatio, dimensionless • Efficiency, Eff, dimensionless <p>Include data for several test points at each rack position operating point.</p> <p>The speed, corrected mass flow rate, rack position, pressure ratio, and efficiency are in the 2nd-6th columns of the data file, respectively. The first and second rows of the data file provide the variable names and units. For example, use this format.</p> <table border="1" data-bbox="764 1524 1471 1730"> <tr> <td>Name:</td> <td>Spd</td> <td>MassFlwRate</td> <td>RackPos</td> <td>PrsRatio</td> <td>Eff</td> </tr> <tr> <td>Unit:</td> <td>rad/s</td> <td>kg/s</td> <td></td> <td></td> <td></td> </tr> <tr> <td>Data:</td> <td>8373.3</td> <td>0.02</td> <td>1</td> <td>1.21</td> <td>0.44</td> </tr> <tr> <td></td> <td>...</td> <td>...</td> <td></td> <td>...</td> <td>...</td> </tr> </table>	Name:	Spd	MassFlwRate	RackPos	PrsRatio	Eff	Unit:	rad/s	kg/s				Data:	8373.3	0.02	1	1.21	0.44	
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Model-Based Calibration Toolbox limits the speed and pressure ratio breakpoint values to the maximum values in the file.																																																		

Task	Description																			
	To filter or edit the data, select Edit in Application . The Model-Based Calibration Toolbox Data Editor opens.																			
Generate response models	<p>Model-Based Calibration Toolbox fits the imported data and generates response models.</p> <table border="1"> <thead> <tr> <th>Turbine type</th> <th colspan="2">Description</th> </tr> </thead> <tbody> <tr> <td rowspan="3">Fixed geometry</td> <td>Data</td> <td>Response Model</td> </tr> <tr> <td>Corrected mass flow rate</td> <td>Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td>Efficiency</td> <td>Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td rowspan="3">Variable geometry</td> <td colspan="2">Model-Based Calibration Toolbox uses a point-by-point test plan to fit the data. For each rack position, the block uses these response models to fit the corrected mass flow rate and efficiency data.</td> </tr> <tr> <td>Data</td> <td>Response Model</td> </tr> <tr> <td>Corrected mass flow rate</td> <td>Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td>Efficiency</td> <td>Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> </tbody> </table> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>	Turbine type	Description		Fixed geometry	Data	Response Model	Corrected mass flow rate	Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i>	Efficiency	Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i>	Variable geometry	Model-Based Calibration Toolbox uses a point-by-point test plan to fit the data. For each rack position, the block uses these response models to fit the corrected mass flow rate and efficiency data.		Data	Response Model	Corrected mass flow rate	Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i>	Efficiency	Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i>
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	Corrected mass flow rate	Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i>																		
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Generate calibration	<p>Model-Based Calibration Toolbox calibrates the response model and generates calibrated tables.</p> <table border="1"> <thead> <tr> <th>Turbine type</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>Fixed geometry</td> <td>Model-Based Calibration Toolbox uses the response models for the corrected mass flow rate and efficiency tables.</td> </tr> <tr> <td>Variable geometry</td> <td>Model-Based Calibration Toolbox fills the corrected mass flow rate and efficiency tables for each rack position. Model-Based Calibration Toolbox then combines the rack position-dependent tables into 3D lookup tables for corrected mass flow rate and efficiency.</td> </tr> </tbody> </table> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>	Turbine type	Description	Fixed geometry	Model-Based Calibration Toolbox uses the response models for the corrected mass flow rate and efficiency tables.	Variable geometry	Model-Based Calibration Toolbox fills the corrected mass flow rate and efficiency tables for each rack position. Model-Based Calibration Toolbox then combines the rack position-dependent tables into 3D lookup tables for corrected mass flow rate and efficiency.													
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Task	Description						
Update block parameters	Update these corrected mass flow rate and efficiency parameters with the calibration.						
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Thermodynamics

The block uses these equations to model the thermodynamics.

Calculation	Equations
Forward mass flow	$\dot{m}_{turb} > 0$ $p_{01} = p_{inlet}$ $p_{02} = p_{outlet}$ $T_{01} = T_{inlet}$ $h_{01} = h_{inlet}$
First law of thermodynamics	$\dot{W}_{turb} = \dot{m}_{turb} c_p (T_{01} - T_{02})$
Isentropic efficiency	$\eta_{turb} = \frac{h_{01} - h_{02}}{h_{01} - h_{02s}} = \frac{T_{01} - T_{02}}{T_{01} - T_{02s}}$
Isentropic outlet temperature, assuming ideal gas, and constant specific heats	$T_{02s} = T_{01} \left(\frac{p_{02}}{p_{01}} \right)^{\frac{\gamma-1}{\gamma}}$
Specific heat ratio	$\gamma = \frac{c_p}{c_p - R}$
Outlet temperature	$T_{02} = T_{01} + \eta_{turb} T_{01} \left\{ 1 - \left(\frac{p_{02}}{p_{01}} \right)^{\frac{\gamma-1}{\gamma}} \right\}$
Heat flows	$q_{in, turb} = \dot{m}_{turb} c_p T_{01}$ $q_{out, turb} = \dot{m}_{turb} c_p T_{02}$

Calculation	Equations
Drive shaft torque	$\tau_{turb} = \frac{\dot{W}_{turb}}{\omega}$

The equations use these variables.

p_{inlet}, p_{01}	Inlet control volume total pressure
T_{inlet}, T_{01}	Inlet control volume total temperature
h_{inlet}, h_{01}	Inlet control volume total specific enthalpy
p_{outlet}, p_{02}	Outlet control volume total pressure
T_{outlet}	Outlet control volume total temperature
h_{outlet}	Outlet control volume total specific enthalpy
\dot{W}_{turb}	Drive shaft power
T_{02}	Temperature exiting the turbine
h_{02}	Outlet total specific enthalpy
\dot{m}_{turb}	Turbine mass flow rate
$q_{in, turb}$	Turbine inlet heat flow rate
$q_{out, turb}$	Turbine outlet heat flow rate
η_{turb}	Turbine isentropic efficiency
T_{02s}	Isentropic outlet total temperature
h_{02s}	Isentropic outlet total specific enthalpy
R	Ideal gas constant
c_p	Specific heat at constant pressure
γ	Specific heat ratio
τ_{turb}	Drive shaft torque

Performance Lookup Tables

The block implements lookup tables based on these equations.

Calculation	Equation	
Corrected mass flow rate	$\dot{m}_{corr} = \dot{m}_{turb} \frac{\sqrt{T_{01}/T_{ref}}}{p_{01}/p_{ref}}$	
Corrected speed	$\omega_{corr} = \frac{\omega}{\sqrt{T_{01}/T_{ref}}}$	
Pressure expansion ratio	$p_r = \frac{p_{01}}{p_{02}}$	
Efficiency lookup table	Fixed geometry (3-D table)	$\eta_{turbfx, tbl} = f(\omega_{corr}, p_r)$
	Variable geometry (3-D table)	$\eta_{turbvr, tbl} = f(\omega_{corr}, p_r, L_{rack})$

Calculation	Equation	
Corrected mass flow lookup table	Fixed geometry (3-D table)	$\dot{m}_{corrfx, tbl} = f(\omega_{corr}, p_r)$
	Variable geometry (3-D table)	$\dot{m}_{corrvr, tbl} = f(\omega_{corr}, p_r, L_{rack})$

The equations use these variables.

p_{01}	Inlet control volume total pressure
p_r	Pressure expansion ratio
p_{02}	Outlet control volume total pressure
P_{ref}	Lookup table reference pressure
T_{01}	Inlet control volume total temperature
T_{ref}	Lookup table reference temperature
\dot{m}_{turb}	Turbine mass flow rate
ω	Drive shaft speed
ω_{corr}	Corrected drive shaft speed
L_{rack}	Variable geometry turbine rack position
$\eta_{turbfx, tbl}$	Efficiency 3-D lookup table for fixed geometry
$\dot{m}_{corrfx, tbl}$	Corrected mass flow rate 3-D lookup table for fixed geometry
$\eta_{turbvr, tbl}$	Efficiency 3-D lookup table for variable geometry
$\dot{m}_{corrvr, tbl}$	Corrected mass flow rate 3-D lookup table for variable geometry

Wastegate

To calculate the wastegate heat and mass flow rates, the Turbine block uses a Flow Restriction block. The Flow Restriction block uses the wastegate flow area.

$$A_{wg} = A_{wgpctcmd} \frac{A_{wgopen}}{100}$$

The equation uses these variables.

$A_{wgpctcmd}$	Wastegate valve area percent command
A_{wg}	Wastegate valve area
A_{wgopen}	Wastegate valve area when fully open

Combined Flow

To represent flow through the wastegate valve and turbine, the block uses these equations.

Calculation	Equations
Blocks not configured with a wastegate valve	$\dot{m}_{wg} = q_{wg} = 0$
Total mass flow rate	$\dot{m}_{total} = \dot{m}_{turb} + \dot{m}_{wg}$

Calculation	Equations
Total heat flow rate	$q_{inlet} = q_{in, turb} + q_{wg}$
	$q_{outlet} = q_{out, turb} + q_{wg}$
Combined temperature exiting the wastegate valve and turbine	$T_{outflw} = \begin{cases} \frac{q_{outlet}}{\dot{m}_{total}c_p} & \dot{m}_{total} > \dot{m}_{thresh} \\ \frac{T_{02} + T_{outflw, wg}}{2} & else \end{cases}$

The block uses the internal signal FlwDir to track the direction of the flow.

The equations use these variables.

\dot{m}_{total}	Total mass flow rate through the wastegate valve and turbine
\dot{m}_{turb}	Turbine mass flow rate
\dot{m}_{wg}	Mass flow rate through the wastegate valve
q_{inlet}	Total inlet heat flow rate
q_{outlet}	Total outlet heat flow rate
$q_{in, turb}$	Turbine inlet heat flow rate
$q_{out, turb}$	Turbine outlet heat flow rate
q_{wg}	Wastegate valve heat flow rate
T_{02}	Temperature exiting the turbine
T_{outflw}	Total temperature exiting the block
$T_{outflw, wg}$	Temperature exiting the wastegate valve
\dot{m}_{thresh}	Mass flow rate threshold to prevent dividing by zero
c_p	Specific heat at constant pressure

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrDriveshft	Power transmitted from the shaft $-\dot{W}_{turb}$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrHeatFlwIn	Heat flow rate at port A q_{outlet}
		PwrHeatFlwOut	Heat flow rate at port B q_{outlet}

Bus Signal		Description	Equations	
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 	PwrLoss	Power loss	$-q_{inlet}$ $-q_{outlet}$ $+ \dot{W}_{turb}$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	<i>Not used</i>		

The equations use these variables.

\dot{W}_{turb}	Drive shaft power
q_{outlet}	Total outlet heat flow rate
q_{inlet}	Total inlet heat flow rate

Ports

Input

Ds — Drive shaft speed

two-way connector port

ShaftSpd — Signal containing the drive shaft angular speed, ω , in rad/s.

A — Inlet pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the inlet control volume:

- InPrs — Pressure, p_{inlet} , in Pa
- InTemp — Temperature, T_{inlet} , in K
- InEnth — Specific enthalpy, h_{inlet} , in J/kg

B — Outlet pressure, temperature, enthalpy, mass fractions

two-way connector port

Bus containing the outlet control volume:

- OutPrs — Pressure, p_{outlet} , in Pa
- OutTemp — Temperature, T_{outlet} , in K
- OutEnth — Specific enthalpy, h_{outlet} , in J/kg

RackPos — Rack position

scalar

Variable geometry turbine rack position, L_{rack} .

Dependencies

To create this port, select Variable geometry for the **Turbine type** parameter.

WgAreaPct — Wastegate area percent

scalar

Wastegate valve area percent, A_{wgpcmd} .

Dependencies

To create this port, select **Include wastegate**.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal			Description	Units
TurbOutletTemp			Temperature exiting the turbine	K
DriveshftPwr			Drive shaft power	W
DriveshftTrq			Drive shaft torque	N·m
TurbMassFlw			Turbine mass flow rate	kg/s
PrsRatio			Pressure ratio	N/A
DriveshftCorrSpd			Corrected drive shaft speed	rad/s
TurbEff			Turbine isentropic efficiency	N/A
CorrMassFlw			Corrected mass flow rate	kg/s
WgArea			Wastegate valve area	m ²
WgMassFlw			Mass flow rate through the wastegate valve	kg/s
WgOutletTemp			Temperature exiting the wastegate valve	K
PwrInfo	PwrTrnsfrd	PwrDriveshft	Power transmitted from the shaft	W
		PwrHeatFlwIn	Heat flow rate at port A	W
		PwrHeatFlwOut	Heat flow rate at port B	W
	PwrNotTrnsfrd	PwrLoss	Power loss	W
	PwrStored		<i>Not used</i>	

Ds — Drive shaft torque

two-way connector port

Trq — Signal containing the drive shaft torque, τ_{turb} , in N·m.

A — Inlet mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing:

- MassFlwRate — Total mass flow rate through wastegate valve and turbine, $-\dot{m}_{total}$, in kg/s
- HeatFlwRate — Total inlet heat flow rate, $-q_{inlet}$, in J/s
- Temp — Total inlet temperature, T_{inlet} , in K
- MassFrac — Mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide
- NOMassFrac — Nitric oxide
- NO2MassFrac — Nitrogen dioxide
- NOxMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

B — Outlet mass flow rate, heat flow rate, temperature, mass fractions

two-way connector port

Bus containing:

- MassFlwRate — Turbine mass flow rate through wastegate valve and turbine, \dot{m}_{turb} , in kg/s
- HeatFlwRate — Total outlet heat flow rate, q_{outlet} , in J/s
- Temp — Total outlet temperature, T_{outflw} , in K
- MassFrac — Mass fractions, dimensionless.

Specifically, a bus with these mass fractions:

- O2MassFrac — Oxygen
- N2MassFrac — Nitrogen
- UnbrndFuelMassFrac — Unburned fuel
- CO2MassFrac — Carbon dioxide
- H2OMassFrac — Water
- COMassFrac — Carbon monoxide

- N0MassFrac — Nitric oxide
- N02MassFrac — Nitrogen dioxide
- N0xMassFrac — Nitric oxide and nitrogen dioxide
- PmMassFrac — Particulate matter
- AirMassFrac — Air
- BrndGasMassFrac — Burned gas

Parameters

Block Options

Turbine type — Select turbine type

Fixed geometry (default) | Variable geometry

Turbine type.

Dependencies

The table summarizes the parameter and port dependencies.

Value	Enables Parameters	Creates Ports
Fixed geometry	<p>Corrected mass flow rate table, mdot_corrfx_tbl</p> <p>Efficiency table, eta_turbfx_tbl</p> <p>Corrected speed breakpoints, w_corrfx_bpts1</p> <p>Pressure ratio breakpoints, Pr_fx_bpts2</p>	None
Variable geometry	<p>Corrected mass flow rate table, mdot_corrvr_tbl</p> <p>Efficiency table, eta_turbvr_tbl</p> <p>Corrected speed breakpoints, w_corrvr_bpts2</p> <p>Pressure ratio breakpoints, Pr_vr_bpts2</p> <p>Rack breakpoints, L_rack_bpts3</p>	RP

Include wastegate — Select

on (default) | off

Dependencies

Selecting the **Include wastegate** parameter enables:

- **Wastegate flow area, A_wgopen**
- **Pressure ratio linearize limit, Plim_wg**

Performance Tables

Calibrate Performance Maps — Calibrate tables with measured data selection

If you have Model-Based Calibration Toolbox, click **Calibrate Performance Maps** to virtually calibrate the corrected mass flow rate and turbine efficiency lookup tables using measured data. The dialog box steps through these tasks.

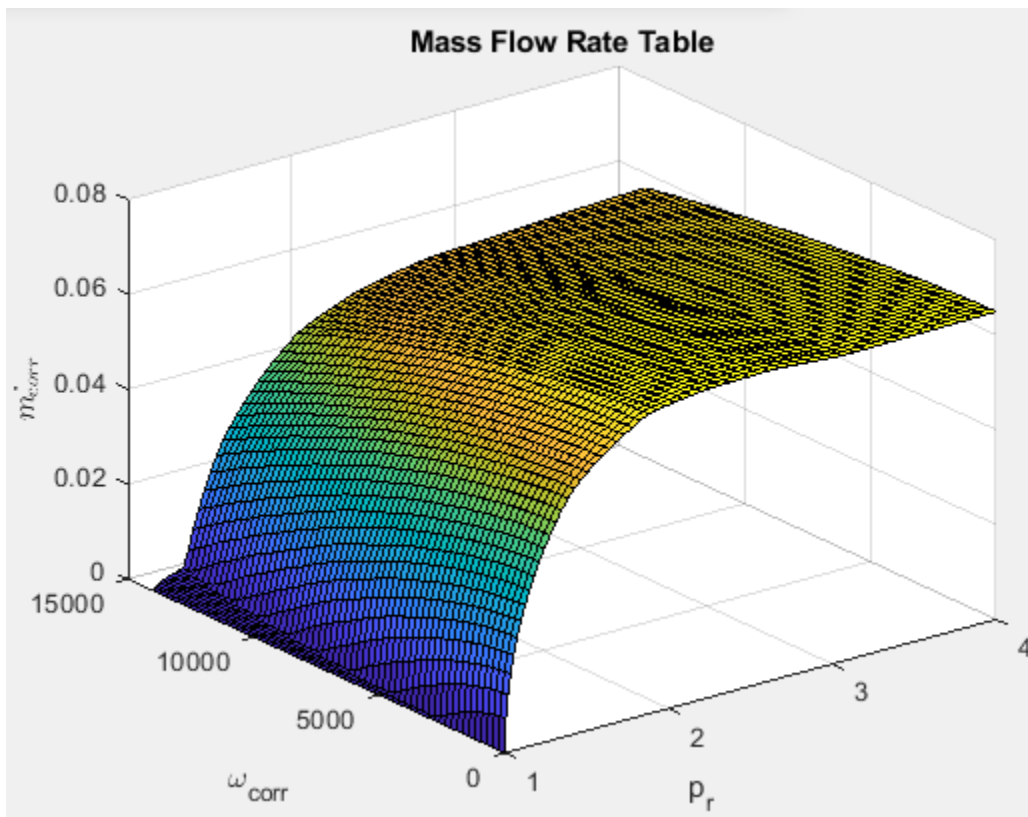
Task	Description																																																	
Import turbine data	Import this turbine data from a file. For more information, see “Using Data” (Model-Based Calibration Toolbox).																																																	
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Generate response models	<p>Model-Based Calibration Toolbox fits the imported data and generates response models.</p> <table border="1" data-bbox="505 457 1471 1192"> <thead> <tr> <th data-bbox="505 457 760 501">Turbine type</th> <th colspan="2" data-bbox="760 457 1471 501">Description</th> </tr> </thead> <tbody> <tr> <td data-bbox="505 501 760 772" rowspan="3">Fixed geometry</td> <td data-bbox="760 501 943 546">Data</td> <td data-bbox="943 501 1471 546">Response Model</td> </tr> <tr> <td data-bbox="760 546 943 657">Corrected mass flow rate</td> <td data-bbox="943 546 1471 657">Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td data-bbox="760 657 943 772">Efficiency</td> <td data-bbox="943 657 1471 772">Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td data-bbox="505 772 760 1192" rowspan="3">Variable geometry</td> <td colspan="2" data-bbox="760 772 1471 926">Model-Based Calibration Toolbox uses a point-by-point test plan to fit the data. For each rack position, the block uses these response models to fit the corrected mass flow rate and efficiency data.</td> </tr> <tr> <td data-bbox="760 926 943 970">Data</td> <td data-bbox="943 926 1471 970">Response Model</td> </tr> <tr> <td data-bbox="760 970 943 1081">Corrected mass flow rate</td> <td data-bbox="943 970 1471 1081">Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> <tr> <td data-bbox="760 1081 943 1192">Efficiency</td> <td data-bbox="943 1081 1471 1192">Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i></td> </tr> </tbody> </table> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>	Turbine type	Description		Fixed geometry	Data	Response Model	Corrected mass flow rate	Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i>	Efficiency	Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i>	Variable geometry	Model-Based Calibration Toolbox uses a point-by-point test plan to fit the data. For each rack position, the block uses these response models to fit the corrected mass flow rate and efficiency data.		Data	Response Model	Corrected mass flow rate	Square root turbine flow model described in <i>Modeling and Control of Engines and Drivelines²</i>	Efficiency	Blade speed ratio (BSR) model described in <i>Modeling and Control of Engines and Drivelines²</i>
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Task	Description						
Update block parameters	Update these corrected mass flow rate and efficiency parameters with the calibration.						
	<table border="1"> <thead> <tr> <th>Turbine type</th> <th>Parameters</th> </tr> </thead> <tbody> <tr> <td>Fixed geometry</td> <td> <ul style="list-style-type: none"> Corrected mass flow rate table, \dot{m}_{corrfx_tbl} Efficiency table, η_{turbfx_tbl} Corrected speed breakpoints, w_{corrfx_bpts1} Pressure ratio breakpoints, Pr_{fx_bpts2} </td> </tr> <tr> <td>Variable geometry</td> <td> <ul style="list-style-type: none"> Corrected mass flow rate table, $\dot{m}_{corrivr_tbl}$ Efficiency table, η_{turivr_tbl} Corrected speed breakpoints, $w_{corrivr_bpts2}$ Pressure ratio breakpoints, Pr_{ivr_bpts2} Rack breakpoints, L_{rack_bpts3} </td> </tr> </tbody> </table>	Turbine type	Parameters	Fixed geometry	<ul style="list-style-type: none"> Corrected mass flow rate table, \dot{m}_{corrfx_tbl} Efficiency table, η_{turbfx_tbl} Corrected speed breakpoints, w_{corrfx_bpts1} Pressure ratio breakpoints, Pr_{fx_bpts2} 	Variable geometry	<ul style="list-style-type: none"> Corrected mass flow rate table, $\dot{m}_{corrivr_tbl}$ Efficiency table, η_{turivr_tbl} Corrected speed breakpoints, $w_{corrivr_bpts2}$ Pressure ratio breakpoints, Pr_{ivr_bpts2} Rack breakpoints, L_{rack_bpts3}
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Corrected mass flow rate table, \dot{m}_{corrfx_tbl} – Lookup table array

Corrected mass flow rate lookup table for fixed geometry, \dot{m}_{corrfx_tbl} , as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , in kg/s.



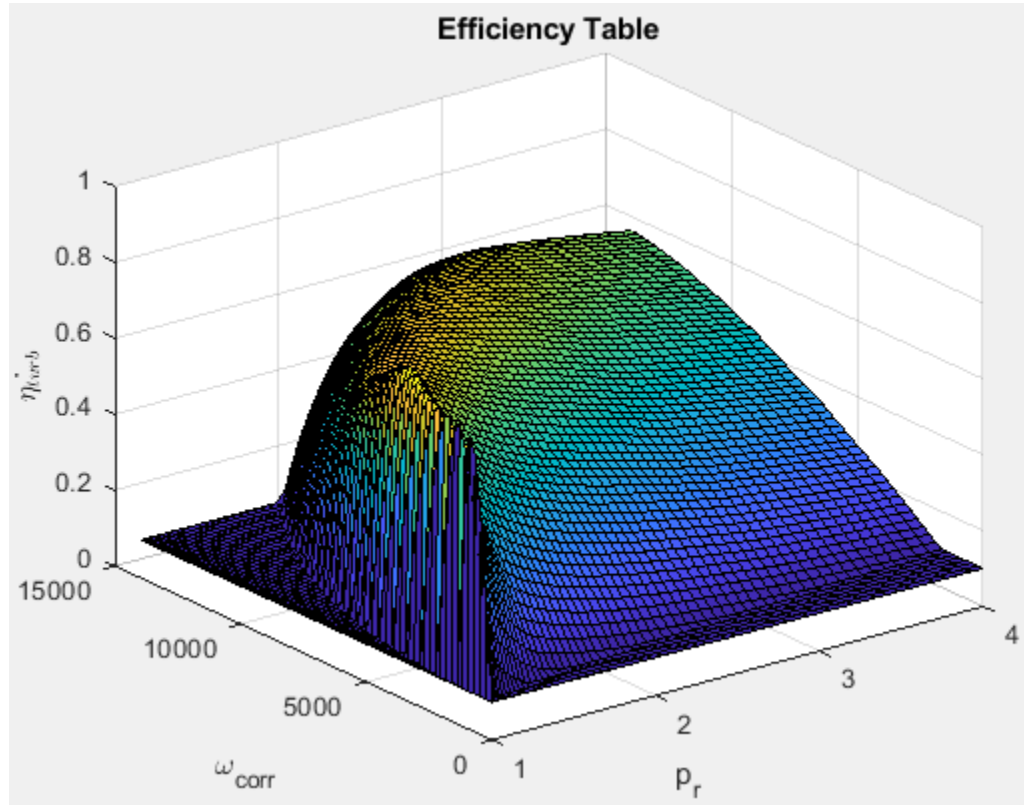
Dependencies

To enable this parameter, select Fixed geometry for the **Turbine type** parameter.

Efficiency table, eta_turbfx_tb — Lookup table

array

Efficiency lookup table for fixed geometry, $\eta_{turbfx,tbl}$, as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , dimensionless.

**Dependencies**

To enable this parameter, select Fixed geometry for the **Turbine type** parameter.

Corrected speed breakpoints, w_corrfx_bpts1 — Fixed geometry

[0 1552 3104 4657 6209 7761 9313 1.087e+04 1.242e+04 1.397e+04] (default) | vector

Corrected drive shaft speed breakpoints for fixed geometry, $\omega_{corrfx,bpts1}$, in rad/s.

Dependencies

To enable this parameter, select Fixed geometry for the **Turbine type** parameter.

Pressure ratio breakpoints, Pr_fx_bpts2 — Fixed geometry

[1 1.333 1.667 2 2.333 2.667 3 3.333 3.667 4] (default) | vector

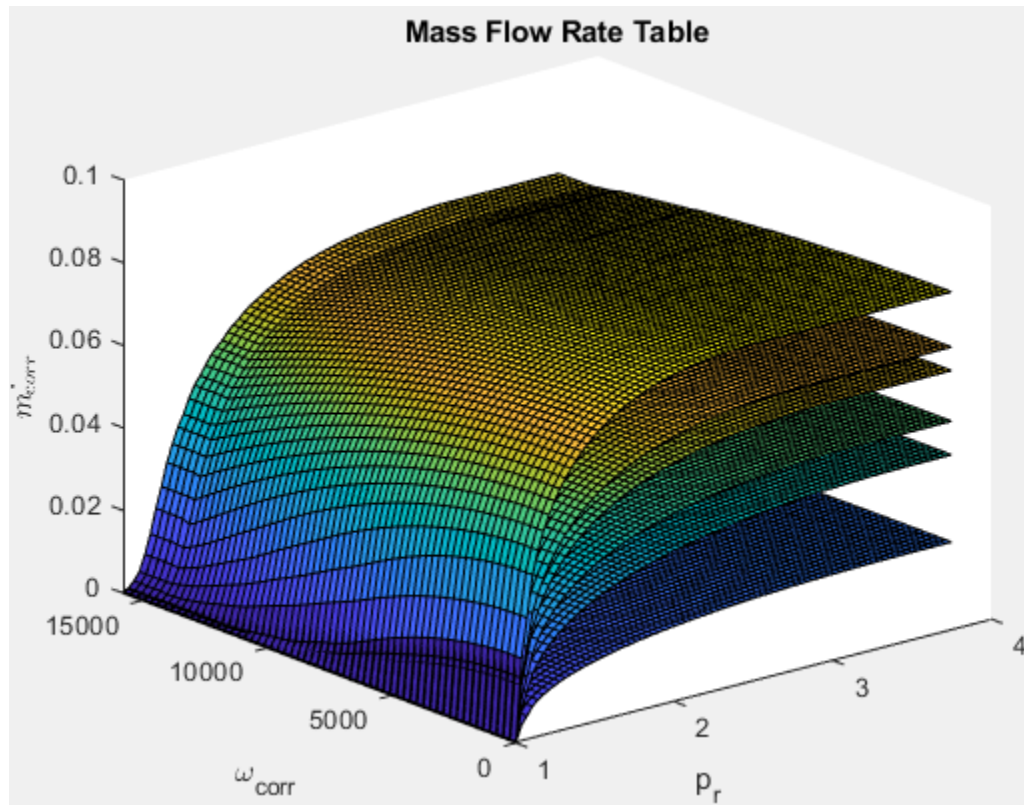
Pressure ratio breakpoints for fixed geometry, $p_{rfx,bpts2}$.

Dependencies

To enable this parameter, select Fixed geometry for the **Turbine type** parameter.

Corrected mass flow rate table, \dot{m}_{corrvr_tbl} – Lookup table array

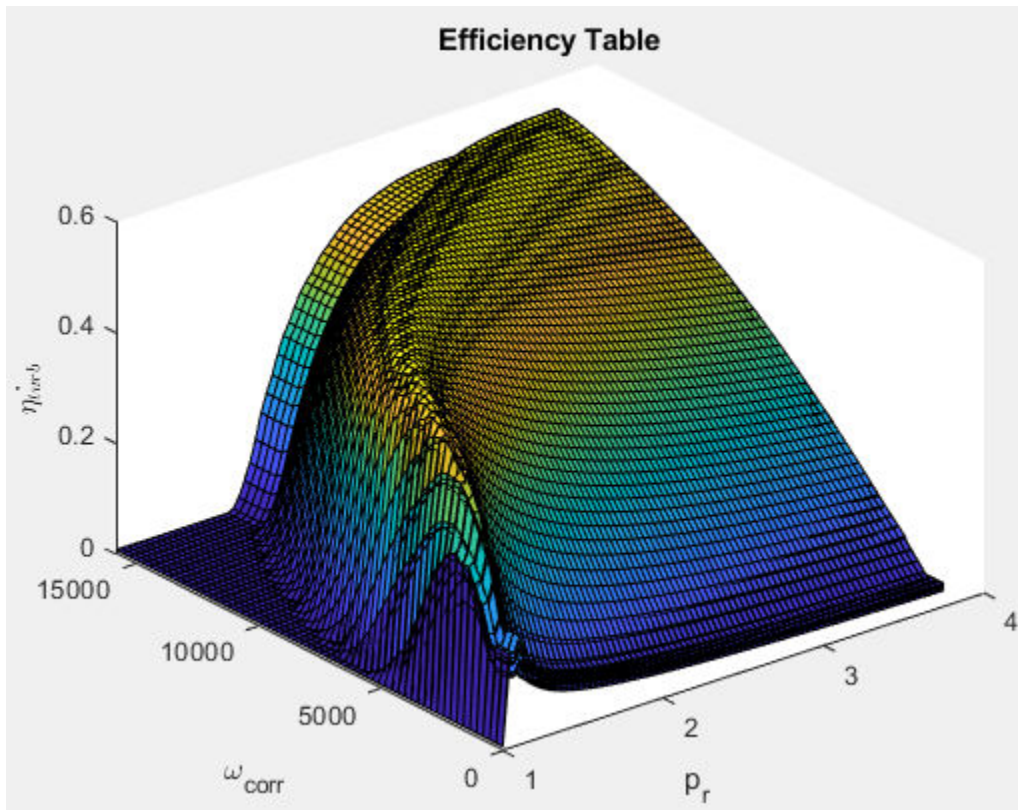
Corrected mass flow rate lookup table for variable geometry, \dot{m}_{corrvr_tbl} , as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , in kg/s.

**Dependencies**

To enable this parameter, select Variable geometry for the **Turbine type** parameter.

Efficiency table, η_{turbvr_tbl} – Lookup table array

Efficiency lookup table for variable geometry, η_{turbvr_tbl} , as a function of corrected driveshaft speed, ω_{corr} , and pressure ratio, p_r , dimensionless.



Dependencies

To enable this parameter, select **Variable geometry** for the **Turbine type** parameter.

Corrected speed breakpoints, w_corrvr_bpts2 — Variable geometry

[0 1752 3504 5257 7009 8761 1.051e+04 1.227e+04 1.402e+04 1.577e+04] (default) | vector

Corrected drive shaft speed breakpoints for variable geometry, $\omega_{corrvr,bpts1}$, in rad/s.

Dependencies

To enable this parameter, select **Variable geometry** for the **Turbine type** parameter.

Pressure ratio breakpoints, Pr_vr_bpts2 — Variable geometry

[1 1.306 1.611 1.917 2.222 2.528 2.833 3.139 3.444 3.75] (default) | vector

Pressure ratio breakpoints for variable geometry.

Dependencies

To enable this parameter, select **Variable geometry** for the **Turbine type** parameter.

Rack breakpoints, L_rack_bpts3 — Variable geometry

[0 0.2 0.3 0.5 0.7 1] (default) | vector

Rack position breakpoints for variable geometry, $L_{rack,bpts3}$.

Dependencies

To enable this parameter, select **Variable geometry** for the **Turbine type** parameter.

Reference temperature, T_ref – Temperature

293.15 (default) | scalar

Performance map reference temperature, T_{ref} , in K.

Reference pressure, P_ref – Pressure

101325 (default) | scalar

Performance map reference pressure, P_{ref} , in Pa.

Wastegate**Wastegate flow area, A_wgopen – Area**

0.0003 (default) | scalar

Area of fully opened wastegate valve, A_{wgopen} , in m^2 .

Dependencies

To enable **Wastegate flow area, A_wgopen**, select the **Include wastegate** parameter.

Pressure ratio linearize limit, Plim_wg – Area, m²

0.95 (default) | scalar

Dependencies

Flow restriction linearization limit, $p_{lim, wg}$.

To enable **Pressure ratio linearize limit, Plim_wg**, select the **Include wastegate** parameter.

Properties**Ideal gas constant, R – Constant**

287 (default) | scalar

Ideal gas constant R , in $J/(kg \cdot K)$.

Specific heat at constant pressure, cp – Specific heat

1005 (default) | scalar

Specific heat at constant pressure, c_p , in $J/(kg \cdot K)$.

Version History

Introduced in R2017a

References

- [1] Heywood, John B. *Internal Combustion Engine Fundamentals*. New York: McGraw-Hill, 1988.
- [2] Eriksson, Lars and Lars Nielsen. *Modeling and Control of Engines and Drivelines*. Chichester, West Sussex, United Kingdom: John Wiley & Sons Ltd, 2014.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Compressor | Boost Drive Shaft

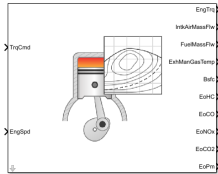
Topics

“Model-Based Calibration Toolbox”

Mapped Core Engine

Steady-state core engine model using lookup tables

Library: Powertrain Blockset / Propulsion / Combustion Engine
Components / Core Engine



Description

The Mapped Core Engine block implements a steady-state core engine model using power, air mass flow, fuel flow, exhaust temperature, efficiency, and emission performance lookup tables. You can use the block for:

- Hardware-in-the-loop (HIL) engine control design.
- Vehicle-level fuel economy and performance simulations.

The block enables you to specify lookup tables for these engine characteristics. The lookup tables are functions of engine load, L , and engine speed N . If you select **Input engine temperature**, the tables are also a function of engine temperature, T .

- Power
- Air
- Fuel
- Temperature
- Efficiency
- Emissions
 - Hydrocarbon (HC)
 - Carbon monoxide (CO)
 - Nitric oxide and nitrogen dioxide (NO_x)
 - Carbon dioxide (CO₂)
 - Particulate matter (PM) emissions

To bound the Mapped Core Engine block output, the block does not extrapolate the lookup table data.

Ports

Input

<TrqCmd> — Engine load

TrqCmd (default)

Engine load, L . Examples of engine load include:

- Commanded torque
- Commanded indicated mean effective pressure (IMEP) in the engine cylinder
- Normalized cylinder air mass
- Injected fuel mass

Dependencies

To specify an engine load port name, on the **Configuration** tab, enter a name in the **Load input port name** parameter field.

<EngSpd> – Engine speed

EngSpd (default)

Engine speed, N .

Dependencies

To specify an engine load port name, on the **Configuration** tab, enter a name in the **Speed input port name** parameter field.

<EngTemp> – Engine temperature

EngTemp (default)

Engine temperature, T .

Dependencies

To create the engine temperature input port name, select **Input engine temperature** parameter field.

To specify an engine load port name, on the **Configuration** tab, enter a name in the **Temperature input port name** parameter field.

Output

<EngTrq> – Power

EngTrq (default)

Engine power, T_{brake} .

Dependencies

- To create this port, on the **Configuration** tab, select **Power**.
- To specify the port name, on the **Power** tab, enter a name in the **Power output port name** parameter field.

<IntkAirMassFlw> – Air mass flow

IntkAirMassFlw (default)

Engine air mass flow, \dot{m}_{intk} .

Dependencies

- To create this port, on the **Configuration** tab, select **Air**.

- To specify the port name, on the **Air** tab, enter a name in the **Air output port name** parameter field.

<FuelMassFlw> – Fuel flow

FuelMassFlw (default)

Engine fuel flow, \dot{m}_{fuel} .**Dependencies**

- To create this port, on the **Configuration** tab, select **Fuel**.
- To specify the port name, on the **Fuel** tab, enter a name in the **Fuel output port name** parameter field.

<ExhManGasTemp> – Exhaust temperature

ExhManGasTemp (default)

Engine exhaust temperature, T_{exh} .**Dependencies**

- To create this port, on the **Configuration** tab, select **Temperature**.
- To specify the port name, on the **Temperature** tab, enter a name in the **Temperature output port name** parameter field.

<Bsfc> – Efficiency

Bsfc (default)

Brake-specific fuel consumption (BSFC), Eff .**Dependencies**

- To create this port, on the **Configuration** tab, select **Efficiency**.
- To specify the port name, on the **Efficiency** tab, enter a name in the **Efficiency output port name** parameter field.

<EoHC> – Hydrocarbon emissions

EoHC (default)

Hydrocarbon emissions, HC .**Dependencies**

- To create this port, on the **Configuration** tab, select **HC**.
- To specify the port name, on the **HC** tab, enter a name in the **HC output port name** parameter field.

<EoCO> – Carbon monoxide emissions

EoCO (default)

Carbon monoxide emissions, CO .**Dependencies**

- To create this port, on the **Configuration** tab, select **CO**.

- To specify the port name, on the **CO** tab, enter a name in the **CO output port name** parameter field.

<EoNOx> – Nitric oxide and nitrogen dioxide emissions

EoNOx (default)

Nitric oxide and nitrogen dioxide emissions, *NOx*.

Dependencies

- To create this port, on the **Configuration** tab, select **NOx**.
- To specify the port name, on the **NOx** tab, enter a name in the **NOx output port name** parameter field.

<EoCO2> – Carbon dioxide emissions

EoCO2 (default)

Carbon dioxide emissions, *CO2*.

Dependencies

- To create this port, on the **Configuration** tab, select **CO2**.
- To specify the port name, on the **CO2** tab, enter a name in the **CO2 output port name** parameter field.

<EoPm> – Particulate matter emissions

EoPm (default)

Particulate matter emissions, *PM*.

Dependencies

- To create this port, on the **Configuration** tab, select **PM**.
- To specify the port name, on the **PM** tab, enter a name in the **PM output port name** parameter field.

Parameters

Configuration

Engine Type – Type of engine image

Compression-ignition (CI) (default) | Spark-ignition (SI)

Type of mapped internal combustion engine image to use in the block.

Load input port name – Name

TrqCmd (default)

Engine load input port name.

Breakpoints for load input – Breakpoints

vector

Breakpoints for engine load input.

Speed input port name – Name

EngSpd (default)

Speed input port name.

Breakpoints for speed input – Breakpoints

vector

Breakpoints for engine speed input.

Temperature input port name – Name

EngTemp (default)

Temperature input port name.

Dependencies

To enable this parameter, select **Input engine temperature**.

Breakpoints for temperature input – Breakpoints

[233.15 273.15 373.15] (default) | vector

Breakpoints for engine temperature input.

Dependencies

To enable this parameter, select **Input engine temperature**.

Output Configuration – Create output ports

on (default)

Create the output ports.

Dependencies

The table summarizes the output ports that are created for each **Output** parameter selection.

Output Selection	Creates Port	Creates Tab
Power	<i>EngTrq</i>	Power
Air	<i>IntkAirMassFlw</i>	Air
Fuel	<i>FuelMassFlw</i>	Fuel
Temperature	<i>ExhManGasTemp</i>	Temperature
Efficiency	<i>Bsfc</i>	Efficiency
HC	<i>EoHC</i>	HC
CO	<i>EoCO</i>	CO
NOx	<i>EoNOx</i>	NOx
CO2	<i>EoCO2</i>	CO2
PM	<i>EoPm</i>	PM

Power

Power output port name – Power

EngTrq (default)

Power output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **Power**.

Power table – Power

array

Power table.

Dependencies

To create this parameter, on the **Configuration** tab, select **Power**.

Air

Air output port name – Air

IntkAirMassFlw (default)

Air mass flow output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **Air**.

Air table – Air

array

Air mass flow table.

Dependencies

To create this parameter, on the **Configuration** tab, select **Air**.

Fuel

Fuel output port name – Fuel

FuelMassFlw (default)

Fuel output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **Fuel**.

Fuel table – Fuel

array

Fuel table.

Dependencies

To create this parameter, on the **Configuration** tab, select **Fuel**.

Temperature

Temperature output port name – Temperature

ExhManGasTemp (default)

Temperature output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **Temperature**.

Temperature table – Temperature

array

Temperature table.

Dependencies

To create this parameter, on the **Configuration** tab, select **Temperature**.

Efficiency

Efficiency output port name – Efficiency

Bsfc (default)

Efficiency output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **Efficiency**.

Efficiency table – Efficiency

array

Efficiency table.

Dependencies

To create this parameter, on the **Configuration** tab, select **Efficiency**.

HC

HC output port name – Hydrocarbon

EoHC (default)

Hydrocarbon output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **HC**.

HC table – Hydrocarbon

array

Hydrocarbon table.

Dependencies

To create this parameter, on the **Configuration** tab, select **HC**.

CO

CO output port name – Carbon dioxide

EoCO (default)

Carbon monoxide output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **CO**.

CO table – Carbon dioxide

array

Carbon dioxide table.

Dependencies

To create this parameter, on the **Configuration** tab, select **CO**.

NOx

NOx output port name – Nitric oxide *NO* and nitrogen dioxide *NO₂*

EoNOx (default)

NOx output port name. NOx is nitric oxide *NO* and nitrogen dioxide *NO₂*.

Dependencies

To create this parameter, on the **Configuration** tab, select **NOx**.

NOx table – Nitric oxide *NO* and nitrogen dioxide *NO₂*

array

NOx emissions table. NOx is nitric oxide *NO* and nitrogen dioxide *NO₂*.

Dependencies

To create this parameter, on the **Configuration** tab, select **NOx**.

CO2

CO2 output port name – Carbon dioxide

EoCO2 (default)

Carbon dioxide output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **CO2**.

CO2 table – Carbon dioxide

array

Carbon dioxide table.

Dependencies

To create this parameter, on the **Configuration** tab, select **CO2**.

PM

PM output port name – Particulate matter

EoPm (default)

Particulate matter output port name.

Dependencies

To create this parameter, on the **Configuration** tab, select **PM**.

PM table – Particulate matter

array

Particulate matter table.

Dependencies

To create this parameter, on the **Configuration** tab, select **PM**.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

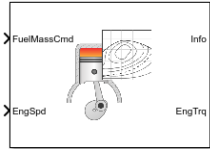
See Also

CI Core Engine | SI Core Engine

Mapped CI Engine

Compression-ignition engine model using lookup tables

Library: Powertrain Blockset / Propulsion / Combustion Engines
Vehicle Dynamics Blockset / Powertrain / Propulsion



Description

The Mapped CI Engine block implements a mapped compression-ignition (CI) engine model using power, air mass flow, fuel flow, exhaust temperature, efficiency, and emission performance lookup tables. You can use the block for:

- Hardware-in-the-loop (HIL) engine control design
- Vehicle-level fuel economy and performance simulations

The lookup tables, developed with the Model-Based Calibration Toolbox, are functions of injected fuel mass, F , engine torque, T , engine speed, N , and engine temperature, $Temp_{Eng}$.

Input Command Setting	Input Engine Temperature Parameter Setting	Lookup Tables
Fuel mass	off	$f(F,N)$
	on	$f(F,N,Temp_{Eng})$
Torque	off	$f(T,N)$
	on	$f(T,N,Temp_{Eng})$

The block enables you to specify lookup tables for these engine characteristics:

- Power
- Air
- Fuel
- Temperature
- Efficiency
- Hydrocarbon (HC) emissions
- Carbon monoxide (CO) emissions
- Nitric oxide and nitrogen dioxide (NOx) emissions
- Carbon dioxide (CO₂) emissions
- Particulate matter (PM) emissions

To bound the Mapped CI Engine block output, the block does not extrapolate the lookup table data.

Virtual Calibration

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the 2D lookup tables using measured data. The dialog box steps through these tasks.

Task	Description									
Import firing data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/mbc/mbctraining/CiEngineData.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <table border="1"> <thead> <tr> <th>Input command</th> <th>Required Data</th> <th>Optional Data</th> </tr> </thead> <tbody> <tr> <td>Fuel mass</td> <td> <ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m </td> <td> <ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s </td> </tr> <tr> <td>Torque</td> <td> <ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m </td> <td> <ul style="list-style-type: none"> CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s </td> </tr> </tbody> </table> <p>Collect firing data at steady-state operating conditions when injectors deliver the fuel. Data should cover the engine speed and torque operating range. Model-Based Calibration Toolbox uses the firing data boundary as the maximum torque.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Input command	Required Data	Optional Data	Fuel mass	<ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s 	Torque	<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m 	<ul style="list-style-type: none"> CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s
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Fuel mass	<ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s 								
Torque	<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m 	<ul style="list-style-type: none"> CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s 								
Import non-firing data	<p>Import this non-firing data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autodemos/projectsrc/CIDynamometer/CalMappedEng/CiEngineData.xlsx</code>.</p> <ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m <p>Collect non-firing (motoring) data at steady-state operating conditions when fuel is cut off. All non-firing torque points must be less than zero. Non-firing data is a function of engine speed only.</p>									
Generate response models	<p>For both firing and non-firing data, the Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>									

Task	Description
Generate calibration	Model-Based Calibration Toolbox calibrates the firing and non-firing response models and generates calibrated tables. To assess or adjust the calibration, select Edit in Application . The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).
Update block parameters	Update the block lookup table and breakpoint parameters with the calibration.

Cylinder Air Mass

The block calculates the normalized cylinder air mass using these equations.

$$M_{Nom} = \frac{P_{std} V_d}{N_{cyl} R_{air} T_{std}}$$

$$L = \frac{\left(\frac{60s}{min}\right) Cps \cdot \dot{m}_{air}}{\left(\frac{1000g}{Kg}\right) N_{cyl} \cdot N \cdot M_{Nom}}$$

The equations use these variables.

L	Normalized cylinder air mass
M_{Nom}	Nominal engine cylinder air mass at standard temperature and pressure, piston at bottom dead center (BDC) maximum volume, in kg
Cps	Crankshaft revolutions per power stroke, rev/stroke
P_{std}	Standard pressure
T_{std}	Standard temperature
R_{air}	Ideal gas constant for air and burned gas mixture
V_d	Displaced volume
N_{cyl}	Number of engine cylinders
N	Engine speed
\dot{m}_{intk}	Engine air mass flow, in g/s

Turbocharger Lag

To model turbocharger lag, select **Include turbocharger lag effect**. Turbocharger lag limits the maximum fuel mass per injection. To model the maximum fuel mass per injection, the block uses a first-order system with a time constant. At low torque, the engine does not require boost to provide sufficient air flow. When the requested fuel mass requires boost, the block uses a time constant to determine the maximum fuel mass per injection. The block uses these equations for the specified **Input command** setting.

Calculation	Input command Parameter Setting	
	Fuel mass	Torque
Dynamic torque	$\frac{dF_{max}}{dt} = \frac{1}{\tau_{eng}}(F_{cmd} - F_{max})$	$\frac{dT_{max}}{dt} = \frac{1}{\tau_{eng}}(T_{cmd} - T_{max})$
Fuel mass per injection or torque - with turbocharger lag	$F = \begin{cases} F_{cmd} & \text{when } F_{cmd} < F_{max} \\ F_{max} & \text{when } F_{cmd} \geq F_{max} \end{cases}$	$T_{target} = \begin{cases} T_{cmd} & \text{when } T_{cmd} < T_{max} \\ T_{max} & \text{when } T_{cmd} \geq T_{max} \end{cases}$
Fuel mass per injection or torque- without turbocharger lag	$F = F_{cmd} = F_{max}$	$T_{target} = T_{cmd} = T_{max}$
Boost time constant	$\tau_{bst} = \begin{cases} \tau_{bst, rising} & \text{when } F_{cmd} > F_{max} \\ \tau_{bst, falling} & \text{when } F_{cmd} \leq F_{max} \end{cases}$	$\tau_{bst} = \begin{cases} \tau_{bst, rising} & \text{when } T_{cmd} > T_{max} \\ \tau_{bst, falling} & \text{when } T_{cmd} \leq T_{max} \end{cases}$
Final time constant	$\tau_{eng} = \begin{cases} \tau_{nat} & \text{when } T_{brake} < f_{bst}(N) \\ \tau_{bst} & \text{when } T_{brake} \geq f_{bst}(N) \end{cases}$	

The equations use these variables.

- T_{brake} Brake torque
- F Fuel mass per injection
- F_{cmd}, F_{max} Commanded and maximum fuel mass per injection, respectively
- $T_{target}, T_{cmd}, T_{max}$ Target, commanded, and maximum torque, respectively
- τ_{bst} Boost time constant
- $\tau_{bst, rising}, \tau_{bst, falling}$ Boost rising and falling time constant, respectively
- τ_{eng} Final time constant
- τ_{nat} Time constant below the boost torque speed line
- $f_{bst}(N)$ Boost torque/speed line
- N Engine speed

Fuel Flow

To calculate the fuel economy for high-fidelity models, the block uses the volumetric fuel flow.

$$Q_{fuel} = \frac{\dot{m}_{fuel}}{\left(\frac{1000kg}{m^3}\right)Sg_{fuel}}$$

The equation uses these variables.

- \dot{m}_{fuel} Fuel mass flow
- Sg_{fuel} Specific gravity of fuel

Q_{fuel} Volumetric fuel flow

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrCrkshft	Crankshaft power $-\tau_{eng}\omega$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrFuel	Fuel input power $\dot{m}_{fuel}LHV$
		PwrLoss	Power loss $\tau_{eng}\omega - \dot{m}_{fuel}LHV$
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 		<i>Not used</i>	

The equations use these variables.

LHV Fuel lower heating value
 ω Engine speed, rad/s
 \dot{m}_{fuel} Fuel mass flow
 τ_{eng} Fuel mass per injection time constant

Ports

Input

FuelMassCmd — Injected fuel mass command

scalar

Injected fuel mass command, F , in mg/inj.

Dependencies

To enable this port, for **Input command**, select Fuel mass.

TrqCmd — Torque command

scalar

Torque command, T , in N·m.

Dependencies

To enable this port, for **Input command**, select Torque.

EngSpd – Engine speed

scalar

Engine speed, N , in rpm.

EngTemp – Engine temperature

scalar

Engine temperature, $Temp_{Eng}$, in K.

Dependencies

To enable this port, select **Input engine temperature**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
IntkGasMassFlw	Engine air mass flow output	kg/s
NrmlzdAirChrg	Normalized engine cylinder air mass	N/A
Afr	Air-fuel ratio (AFR)	N/A
FuelMassFlw	Engine fuel flow output	kg/s
FuelVolFlw	Volumetric fuel flow	m ³ /s
ExhManGasTemp	Engine exhaust gas temperature	K
EngTrq	Engine torque output	N·m
EngSpd	Engine speed	rpm
CrkAng	Engine crankshaft absolute angle $\int_0^{(360)Cps} EngSpd \frac{180}{30} d\theta$ where Cps is crankshaft revolutions per power stroke.	degrees crank angle
Bsfc	Engine brake-specific fuel consumption (BSFC)	g/kWh
EoHC	Engine out hydrocarbon emission mass flow	kg/s
EoCO	Engine out carbon monoxide emission mass flow rate	kg/s
EoNOx	Engine out nitric oxide and nitrogen dioxide emissions mass flow	kg/s
EoCO2	Engine out carbon dioxide emission mass flow	kg/s

Signal			Description	Units
EoPM			Engine out particulate matter emission mass flow	kg/s
PwrInfo	PwrTrnsfrd	PwrCrkshft	Crankshaft power	W
	PwrNotTrnsfrd	PwrFuel	Fuel input power	W
		PwrLoss	Power loss	W
	PwrStored		<i>Not used</i>	

EngTrq – Power

scalar

Engine power, T_{brake} , in N·m.

Parameters

Block Options

Input command – Table functions

Fuel mass (default) | Torque

The lookup tables, developed with the Model-Based Calibration Toolbox, are functions of injected fuel mass, F , engine torque, T , engine speed, N , and engine temperature, $Temp_{Eng}$.

Input Command Setting	Input Engine Temperature Parameter Setting	Lookup Tables
Fuel mass	off	$f(F,N)$
	on	$f(F,N,Temp_{Eng})$
Torque	off	$f(T,N)$
	on	$f(T,N,Temp_{Eng})$

Dependencies

- Selecting Fuel mass enables **Breakpoints for commanded fuel mass input, f_tbrake_f_bpt.**
- Selecting Torque enables **Breakpoints for commanded torque input, f_tbrake_t_bpt.**
- Selecting **Input engine temperature** enables **Breakpoints for temperature input, f_tbrake_engtmp_bpt.**

Include turbocharger lag effect – Increase time constant

off (default)

To model turbocharger lag, select **Include turbocharger lag effect**. Turbocharger lag limits the maximum fuel mass per injection. To model the maximum fuel mass per injection, the block uses a first-order system with a time constant. At low torque, the engine does not require boost to provide sufficient air flow. When the requested fuel mass requires boost, the block uses a time constant to determine the maximum fuel mass per injection. The block uses these equations for the specified **Input command** setting.

Calculation	Input command Parameter Setting	
	Fuel mass	Torque
Dynamic torque	$\frac{dF_{max}}{dt} = \frac{1}{\tau_{eng}}(F_{cmd} - F_{max})$	$\frac{dT_{max}}{dt} = \frac{1}{\tau_{eng}}(T_{cmd} - T_{max})$
Fuel mass per injection or torque - with turbocharger lag	$F =$ $\begin{cases} F_{cmd} & \text{when } F_{cmd} < F_{max} \\ F_{max} & \text{when } F_{cmd} \geq F_{max} \end{cases}$	$T_{target} =$ $\begin{cases} T_{cmd} & \text{when } T_{cmd} < T_{max} \\ T_{max} & \text{when } T_{cmd} \geq T_{max} \end{cases}$
Fuel mass per injection or torque- without turbocharger lag	$F = F_{cmd} = F_{max}$	$T_{target} = T_{cmd} = T_{max}$
Boost time constant	$\tau_{bst} =$ $\begin{cases} \tau_{bst, rising} & \text{when } F_{cmd} > F_{max} \\ \tau_{bst, falling} & \text{when } F_{cmd} \leq F_{max} \end{cases}$	$\tau_{bst} =$ $\begin{cases} \tau_{bst, rising} & \text{when } T_{cmd} > T_{max} \\ \tau_{bst, falling} & \text{when } T_{cmd} \leq T_{max} \end{cases}$
Final time constant	$\tau_{eng} = \begin{cases} \tau_{nat} & \text{when } T_{brake} < f_{bst}(N) \\ \tau_{bst} & \text{when } T_{brake} \geq f_{bst}(N) \end{cases}$	

The equations use these variables.

T_{brake}	Brake torque
F	Fuel mass per injection
F_{cmd}, F_{max}	Commanded and maximum fuel mass per injection, respectively
$T_{target}, T_{cmd}, T_{max}$	Target, commanded, and maximum torque, respectively
τ_{bst}	Boost time constant
$\tau_{bst, rising}, \tau_{bst, falling}$	Boost rising and falling time constant, respectively
τ_{eng}	Final time constant
τ_{nat}	Time constant below the boost torque speed line
$f_{bst}(N)$	Boost torque/speed line
N	Engine speed

Dependencies

Selecting **Include turbocharger lag effect** enables these parameters:

- **Boost torque line, f_tbrake_bst**
- **Time constant below boost line, tau_nat**
- **Rising maximum fuel mass boost time constant, tau_bst_rising**
- **Falling maximum fuel mass boost time constant, tau_bst_falling**

Input engine temperature – Create input port

off (default) | on

Select this to create the EngTemp input port.

The lookup tables, developed with the Model-Based Calibration Toolbox, are functions of injected fuel mass, F , engine torque, T , engine speed, N , and engine temperature, $Temp_{Eng}$.

Input Command Setting	Input Engine Temperature Parameter Setting	Lookup Tables
Fuel mass	off	$f(F,N)$
	on	$f(F,N,Temp_{Eng})$
Torque	off	$f(T,N)$
	on	$f(T,N,Temp_{Eng})$

Configuration

Calibrate Maps – Calibrate tables with measured data selection

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the 2D lookup tables using measured data. The dialog box steps through these tasks.

Task	Description								
Import firing data	Import this loss data from a file. For example, open <code><matlabroot>/toolbox/mbc/mbctraining/CiEngineData.xlsx</code> .								
	For more information, see “Using Data” (Model-Based Calibration Toolbox).								
	<table border="1"> <thead> <tr> <th>Input command</th> <th>Required Data</th> <th>Optional Data</th> </tr> </thead> <tbody> <tr> <td>Fuel mass</td> <td> <ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m </td> <td> <ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s </td> </tr> <tr> <td>Torque</td> <td> <ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m </td> <td> <ul style="list-style-type: none"> CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s </td> </tr> </tbody> </table>	Input command	Required Data	Optional Data	Fuel mass	<ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s 	Torque	<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m
Input command	Required Data	Optional Data							
Fuel mass	<ul style="list-style-type: none"> Engine speed, rpm Commanded fuel mass per injection, mg Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s 							
Torque	<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m 	<ul style="list-style-type: none"> CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s 							
Collect firing data at steady-state operating conditions when injectors deliver the fuel. Data should cover the engine speed and torque operating range. Model-Based Calibration Toolbox uses the firing data boundary as the maximum torque.									
To filter or edit the data, select Edit in Application . The Model-Based Calibration Toolbox Data Editor opens.									

Task	Description
Import non-firing data	<p>Import this non-firing data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autodemos/projectsrc/CIDynamometer/CalMappedEng/CiEngineData.xlsx</code>.</p> <ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m <p>Collect non-firing (motoring) data at steady-state operating conditions when fuel is cut off. All non-firing torque points must be less than zero. Non-firing data is a function of engine speed only.</p>
Generate response models	<p>For both firing and non-firing data, the Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>
Generate calibration	<p>Model-Based Calibration Toolbox calibrates the firing and non-firing response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>
Update block parameters	<p>Update the block lookup table and breakpoint parameters with the calibration.</p>

Dependencies

To enable this parameter, clear **Input engine temperature**.

Breakpoints for commanded fuel mass input, f_tbrake_f_bpt — Breakpoints

1-by-M vector

Breakpoints, in mg/inj.

Dependencies

Setting **Input command** to Fuel mass enables this parameter.

Breakpoints for commanded torque input, f_tbrake_t_bpt — Breakpoints

1-by-M vector

Breakpoints, in N·m.

Dependencies

Setting **Input command** to Torque enables this parameter.

Breakpoints for engine speed input, f_tbrake_n_bpt — Breakpoints

1-by-N vector

Breakpoints, in rpm.

Breakpoints for temperature input, f_tbrake_engtmp_bpt – Breakpoints
[233.15 273.15 373.15] (default) | 1-by-L vector

Breakpoints, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

Number of cylinders, NCyl – Number
4 (default) | scalar

Number of cylinders.

Crank revolutions per power stroke, Cps – Crank revolutions
2 (default) | scalar

Crank revolutions per power stroke.

Total displaced volume, Vd – Volume
0.0015 (default) | scalar

Volume displaced by engine, in m^3 .

Fuel lower heating value, Lhv – Heating value
45e6 (default) | scalar

Fuel lower heating value, LHV , in J/kg.

Fuel specific gravity, Sg – Specific gravity
0.832 (default) | scalar

Specific gravity of fuel, Sg_{fuel} , dimensionless.

Ideal gas constant air, Rair – Constant
287 (default) | scalar

Ideal gas constant of air and residual gas entering the engine intake port, in J/(kg·K).

Air standard pressure, Pstd – Pressure
101325 (default) | scalar

Standard air pressure, in Pa.

Air standard temperature, Tstd – Temperature
293.15 (default) | scalar

Standard air temperature, in K.

Boost torque line, f_tbrake_bst – Boost lag
[90, 95, 95, 95, 96, 100, 104, 104, 104, 100, 95, 85, 75, 67, 60, 55] (default) | 1-by-M vector

Boost torque line, $f_{bst}(N)$, in N·m.

Dependencies

To enable this parameter, select **Include turbocharger lag effect**.

Time constant below boost line – Time constant below

0.1 (default) | scalar

Time constant below boost line, τ_{nat} , in s.**Dependencies**To enable this parameter, select **Include turbocharger lag effect**.**Rising maximum fuel mass boost time constant, tau_bst_rising – Rising time constant**

1.0 (default) | scalar

Rising maximum fuel mass boost time constant, $\tau_{bst,rising}$, in s.**Dependencies**To enable this parameter, select **Include turbocharger lag effect**.**Falling maximum fuel mass boost time constant, tau_bst_falling – Falling time constant**

0.7 (default) | scalar

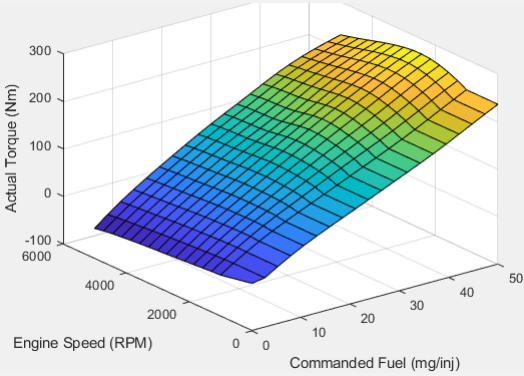
Falling maximum fuel mass boost time constant, $\tau_{bst,falling}$, in s.**Dependencies**To enable this parameter, select **Include turbocharger lag effect**.**Turbocharger time constant blend fuel mass fraction, f_blend_frac – Time constant**

0.01 (default) | scalar

Turbocharger time constant blend fuel mass fraction, in s.

DependenciesTo enable this parameter, select **Include turbocharger lag effect**.**Power****Brake torque map, f_tbrake – 2D lookup table**

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine brake torque lookup table is a function of commanded fuel mass and engine speed, $T_{brake} = f(F, N)$, where:</p> <ul style="list-style-type: none"> • T_{brake} is engine torque, in N·m. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The engine brake torque lookup table is a function of target torque and engine speed, $T_{brake} = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • T_{brake} is engine torque, in N·m. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot brake torque map – Plot table button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Brake torque map, f_tbrake_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine brake torque lookup table is a function of commanded fuel mass and engine speed, $T_{brake} = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • T_{brake} is engine torque, in N·m. • F is commanded fuel mass, in mg per injection. • $Temp_{Eng}$ is engine temperature, in K.

Input Command Setting	Description
Torque	<p>The engine brake torque lookup table is a function of target torque and engine speed, $T_{brake} = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • T_{brake} is engine torque, in N·m. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

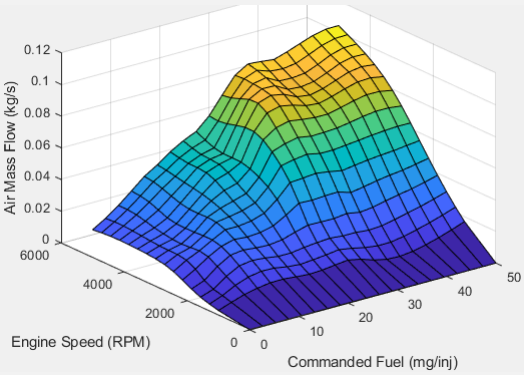
Dependencies

To enable this parameter, select **Input engine temperature**.

Air

Air mass flow map, f_air – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The air mass flow lookup table is a function of commanded fuel mass and engine speed, $\dot{m}_{intk} = f(F_{max}, N)$, where:</p> <ul style="list-style-type: none"> • \dot{m}_{intk} is engine air mass flow, in kg/s. • F_{max} is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The air mass flow lookup table is a function of maximum torque and engine speed, $\dot{m}_{intk} = f(T_{max}, N)$, where:</p> <ul style="list-style-type: none"> • \dot{m}_{intk} is engine air mass flow, in kg/s. • T_{max} is maximum torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot air mass map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Air mass flow map, **f_air_3d** – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The air mass flow lookup table is a function of commanded fuel mass and engine speed, $\dot{m}_{intk} = f(F_{max}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • \dot{m}_{intk} is engine air mass flow, in kg/s. • F_{max} is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The air mass flow lookup table is a function of maximum torque and engine speed, $\dot{m}_{intk} = f(T_{max}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • \dot{m}_{intk} is engine air mass flow, in kg/s. • T_{max} is maximum torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

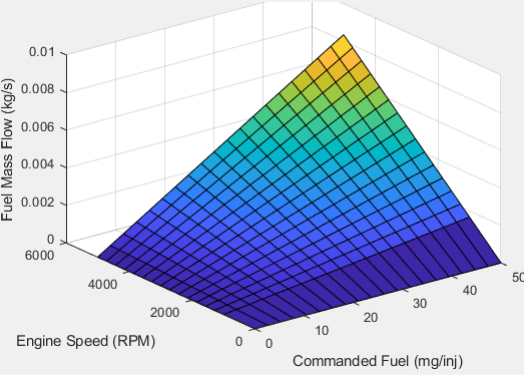
Dependencies

To enable this parameter, select **Input engine temperature**.

Fuel

Fuel flow map, **f_fuel** – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine fuel flow lookup table is a function of commanded fuel mass and engine speed, $MassFlow = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $MassFlow$ is engine fuel mass flow, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The engine fuel flow lookup table is a function of target torque and engine speed, $MassFlow = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $MassFlow$ is engine fuel mass flow, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot fuel flow map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Fuel flow map, f_fuel_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine fuel flow lookup table is a function of commanded fuel mass, engine speed, and engine temperature, $MassFlow = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $MassFlow$ is engine fuel mass flow, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine fuel flow lookup table is a function of target torque and engine speed, and engine temperature, $MassFlow = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $MassFlow$ is engine fuel mass flow, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

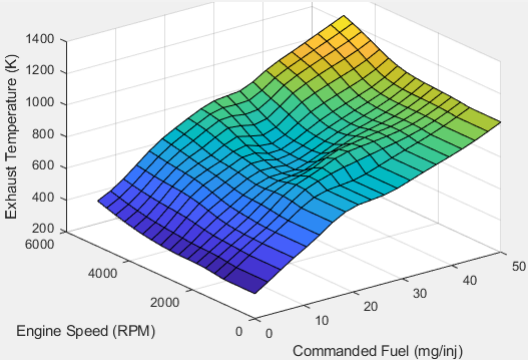
Dependencies

To enable this parameter, select **Input engine temperature**.

Temperature

Exhaust temperature map, f_{texh} – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine exhaust temperature table is a function of commanded fuel mass and engine speed, $T_{exh} = f(F, N)$, where:</p> <ul style="list-style-type: none"> • T_{exh} is exhaust temperature, in K. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 

Input Command Setting	Description
Torque	<p>The engine exhaust temperature table is a function of target torque and engine speed, $T_{exh} = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • T_{exh} is exhaust temperature, in K. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot exhaust temperature map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Exhaust temperature map, f_texh_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine exhaust temperature table is a function of commanded fuel mass and engine speed, $T_{exh} = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • T_{exh} is exhaust temperature, in K. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine exhaust temperature table is a function of target torque and engine speed, $T_{exh} = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • T_{exh} is exhaust temperature, in K. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

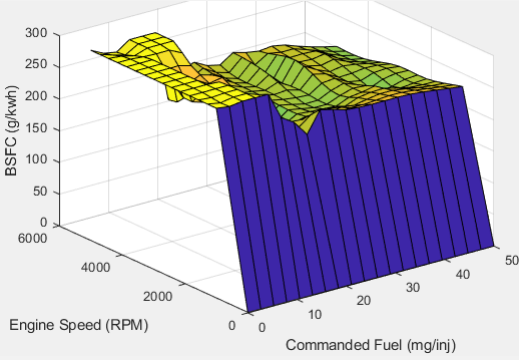
Dependencies

To enable this parameter, select **Input engine temperature**.

Efficiency

BSFC map, f_eff – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The brake-specific fuel consumption (BSFC) efficiency is a function of commanded fuel mass and engine speed, $BSFC = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $BSFC$ is BSFC, in g/kWh. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The brake-specific fuel consumption (BSFC) efficiency is a function of target torque and engine speed, $BSFC = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $BSFC$ is BSFC, in g/kWh. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot BSFC map – Plot table button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

BSFC map, f_eff_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The brake-specific fuel consumption (BSFC) efficiency is a function of commanded fuel mass and engine speed, $BSFC = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $BSFC$ is BSFC, in g/kWh. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

Input Command Setting	Description
Torque	<p>The brake-specific fuel consumption (BSFC) efficiency is a function of target torque and engine speed, $BSFC = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $BSFC$ is BSFC, in g/kWh. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

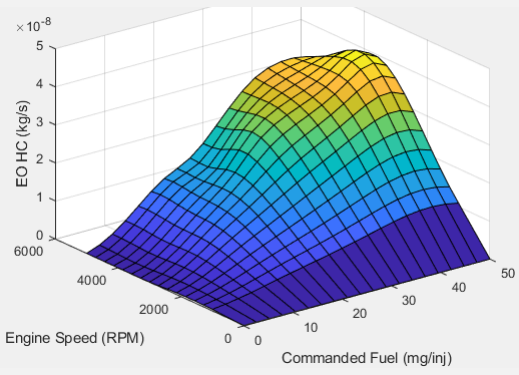
Dependencies

To enable this parameter, select **Input engine temperature**.

HC

E0 HC map, f_hc – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine-out hydrocarbon emissions are a function of commanded fuel mass and engine speed, $EO\ HC = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The engine-out hydrocarbon emissions are a function of target torque and engine speed, $EO\ HC = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot E0 HC map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 HC map, f_{hc_3d} — 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine-out hydrocarbon emissions are a function of commanded fuel mass and engine speed, $EO\ HC = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine-out hydrocarbon emissions are a function of target torque and engine speed, $EO\ HC = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

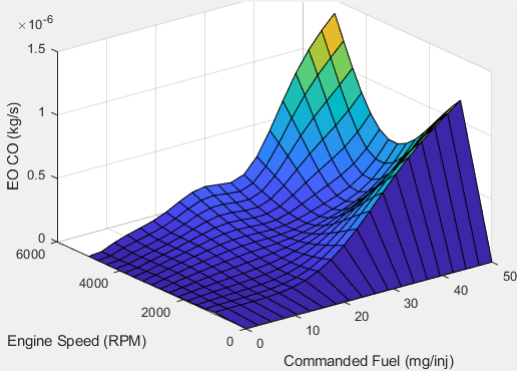
Dependencies

To enable this parameter, select **Input engine temperature**.

CO

E0 CO map, f_{co} — 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine-out carbon monoxide emissions are a function of commanded fuel mass and engine speed, $EO\ CO = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ CO$ is engine-out carbon monoxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The engine-out carbon monoxide emissions are a function of target torque and engine speed, $EO\ CO = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ CO$ is engine-out carbon monoxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot EO CO map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

EO CO map, f_co_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine-out carbon monoxide emissions are a function of commanded fuel mass and engine speed, $EO\ CO = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ CO$ is engine-out carbon monoxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine-out carbon monoxide emissions are a function of target torque and engine speed, $EO\ CO = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ CO$ is engine-out carbon monoxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

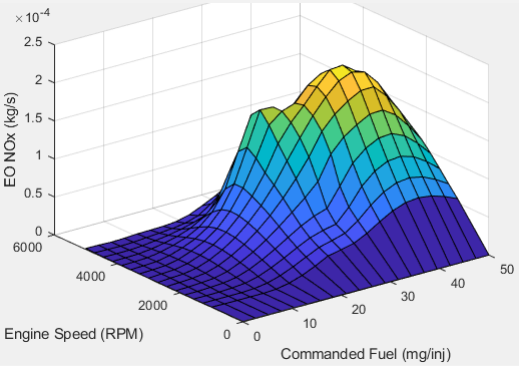
Dependencies

To enable this parameter, select **Input engine temperature**.

NOx

EO NOx map, f_{nox} — 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine-out nitric oxide and nitrogen dioxide emissions are a function of commanded fuel mass and engine speed, $EO\ NOx = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ NOx$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 

Input Command Setting	Description
Torque	<p>The engine-out nitric oxide and nitrogen dioxide emissions are a function of target torque and engine speed, $EO\ NO_x = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ NO_x$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot EO NOx map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

EO NOx map, f_nox_3d – 3D lookup table

M-by-N-by-L array

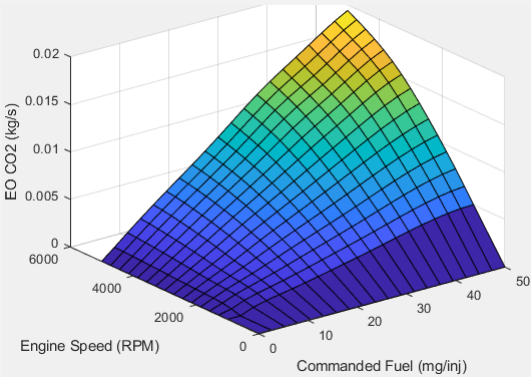
Input Command Setting	Description
Fuel mass	<p>The engine-out nitric oxide and nitrogen dioxide emissions are a function of commanded fuel mass, engine speed, and engine temperature, $EO\ NO_x = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ NO_x$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine-out nitric oxide and nitrogen dioxide emissions are a function of target torque, engine speed, and engine temperature, $EO\ NO_x = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ NO_x$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

CO2**E0 CO2 map, f_co2 – 2D lookup table**

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine-out carbon dioxide emissions are a function of commanded fuel mass and engine speed, $EO\ CO_2 = f(F, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ CO_2$ is engine-out carbon dioxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. 
Torque	<p>The engine-out carbon dioxide emissions are a function of target torque and engine speed, $EO\ CO_2 = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ CO_2$ is engine-out carbon dioxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot CO2 map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 CO2 map, f_co2_3d – 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine-out carbon dioxide emissions are a function of commanded fuel mass, engine speed, and engine temperature, $EO\ CO_2 = f(F, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ CO_2$ is engine-out carbon dioxide emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine-out carbon dioxide emissions are a function of target torque, engine speed, and engine temperature, $EO\ CO_2 = f(T_{target}, N, Temp_{Eng})$, where:</p> <ul style="list-style-type: none"> • $EO\ CO_2$ is engine-out carbon dioxide emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

PM

E0 PM map, f_pm – 2D lookup table

M-by-N matrix

Input Command Setting	Description
Fuel mass	<p>The engine-out PM emissions are a function of commanded fuel mass and engine speed, where:</p> <ul style="list-style-type: none"> • $EO\ PM$ is engine-out PM emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm.
Torque	<p>The engine-out PM emissions are a function of target torque and engine speed, $EO\ PM = f(T_{target}, N)$, where:</p> <ul style="list-style-type: none"> • $EO\ PM$ is engine-out PM emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot E0 PM map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

EO PM map, f_{pm_3d} — 3D lookup table

M-by-N-by-L array

Input Command Setting	Description
Fuel mass	<p>The engine-out PM emissions are a function of commanded fuel mass, engine speed, and engine temperature, where:</p> <ul style="list-style-type: none"> • $EO\ PM$ is engine-out PM emissions, in kg/s. • F is commanded fuel mass, in mg per injection. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.
Torque	<p>The engine-out PM emissions are a function of target torque, engine speed, and engine temperature, $EO\ PM = f(T_{target}, N, T)$, where:</p> <ul style="list-style-type: none"> • $EO\ PM$ is engine-out PM emissions, in kg/s. • T_{target} is target torque, in N·m. • N is engine speed, in rpm. • $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

Version History

Introduced in R2017a

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

See Also

CI Core Engine | Mapped Motor | Mapped SI Engine

Topics

“Generate Mapped CI Engine from a Spreadsheet”

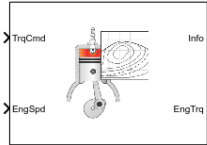
“Engine Calibration Maps”

“Model-Based Calibration Toolbox”

Mapped SI Engine

Spark-ignition engine model using lookup tables

Library: Powertrain Blockset / Propulsion / Combustion Engines
Vehicle Dynamics Blockset / Powertrain / Propulsion



Description

The Mapped SI Engine block implements a mapped spark-ignition (SI) engine model using power, air mass flow, fuel flow, exhaust temperature, efficiency, and emission performance lookup tables. You can use the block for:

- Hardware-in-the-loop (HIL) engine control design
- Vehicle-level fuel economy and performance simulations

The block enables you to specify lookup tables for these engine characteristics. The lookup tables, developed with the Model-Based Calibration Toolbox, are functions of commanded torque, T_{cmd} , brake torque, T_{brake} , and engine speed, N . If you select **Input engine temperature**, the tables are also a function of engine temperature, $Temp_{Eng}$.

Table	Input Engine Temperature Parameter Setting	
	off	on
Power	$f(T_{cmd}, N)$	$f(T_{cmd}, N, Temp_{Eng})$
Air	$f(T_{brake}, N)$	$f(T_{brake}, N, Temp_{Eng})$
Fuel		
Temperature		
Efficiency		
HC		
CO		
NOx		
CO2		
PM		

To bound the Mapped SI Engine block output, the block does not extrapolate the lookup table data.

Virtual Calibration

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the 2D lookup tables using measured data. The dialog box steps through these tasks.

Task	Description				
Import firing data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/mbc/mbctraining/SiEngineData.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <table border="1" data-bbox="505 447 1466 873"> <thead> <tr> <th data-bbox="505 447 862 487">Required Data</th> <th data-bbox="862 447 1466 487">Optional Data</th> </tr> </thead> <tbody> <tr> <td data-bbox="505 487 862 873"> <ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m </td> <td data-bbox="862 487 1466 873"> <ul style="list-style-type: none"> • Air mass flow rate, kg/s • Brake specific fuel consumption, g/(kW·h) • CO₂ mass flow rate, kg/s • CO mass flow rate, kg/s • Exhaust temperature, K • Fuel mass flow rate, kg/s • HC mass flow rate, kg/s • NO_x mass flow rate, kg/s • Particulate matter mass flow rate, kg/s </td> </tr> </tbody> </table> <p>Collect firing data at steady-state operating conditions when injectors deliver the fuel. Data should cover the engine speed and torque operating range. Model-Based Calibration Toolbox uses the firing data boundary as the maximum torque.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Required Data	Optional Data	<ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m 	<ul style="list-style-type: none"> • Air mass flow rate, kg/s • Brake specific fuel consumption, g/(kW·h) • CO₂ mass flow rate, kg/s • CO mass flow rate, kg/s • Exhaust temperature, K • Fuel mass flow rate, kg/s • HC mass flow rate, kg/s • NO_x mass flow rate, kg/s • Particulate matter mass flow rate, kg/s
Required Data	Optional Data				
<ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m 	<ul style="list-style-type: none"> • Air mass flow rate, kg/s • Brake specific fuel consumption, g/(kW·h) • CO₂ mass flow rate, kg/s • CO mass flow rate, kg/s • Exhaust temperature, K • Fuel mass flow rate, kg/s • HC mass flow rate, kg/s • NO_x mass flow rate, kg/s • Particulate matter mass flow rate, kg/s 				
Import non-firing data	<p>Import this non-firing data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autodemos/projectsrc/SIDynamometer/CalMappedEng/SiEngineData.xlsx</code>.</p> <ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m <p>Collect non-firing (motoring) data at steady-state operating conditions when fuel is cut off. All non-firing torque points must be less than zero. Non-firing data is a function of engine speed only.</p>				
Generate response models	<p>For both firing and non-firing data, the Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>				
Generate calibration	<p>Model-Based Calibration Toolbox calibrates the firing and non-firing response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>				

Task	Description
Update block parameters	Update the block lookup table and breakpoint parameters with the calibration.

Cylinder Air Mass

The block calculates the normalized cylinder air mass using these equations.

$$M_{Nom} = \frac{P_{std} V_d}{N_{cyl} R_{air} T_{std}}$$

$$L = \frac{\left(\frac{60s}{min}\right) Cps \cdot \dot{m}_{air}}{\left(\frac{1000g}{Kg}\right) N_{cyl} \cdot N \cdot M_{Nom}}$$

The equations use these variables.

L	Normalized cylinder air mass
M_{Nom}	Nominal engine cylinder air mass at standard temperature and pressure, piston at bottom dead center (BDC) maximum volume, in kg
Cps	Crankshaft revolutions per power stroke, rev/stroke
P_{std}	Standard pressure
T_{std}	Standard temperature
R_{air}	Ideal gas constant for air and burned gas mixture
V_d	Displaced volume
N_{cyl}	Number of engine cylinders
N	Engine speed
\dot{m}_{intk}	Engine air mass flow, in g/s

Turbocharger Lag

To model turbocharger lag, select **Include turbocharger lag effect**. During throttle control, the time constant models the manifold filling and emptying dynamics. When the torque request requires a turbocharger boost, the block uses a larger time constant to represent the turbocharger lag. The block uses these equations.

Dynamic torque	$\frac{dT_{brake}}{dt} = \frac{1}{\tau_{eng}}(T_{stdy} - T_{brake})$
Boost time constant	$\tau_{bst} = \begin{cases} \tau_{bst, rising} & \text{when } T_{stdy} > T_{brake} \\ \tau_{bst, falling} & \text{when } T_{stdy} \leq T_{brake} \end{cases}$
Final time constant	$\tau_{eng} = \begin{cases} \tau_{thr} & \text{when } T_{brake} < f_{bst}(N) \\ \tau_{bst} & \text{when } T_{brake} \geq f_{bst}(N) \end{cases}$

The equations use these variables.

T_{brake}	Brake torque
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T_{stdy}	Steady-state target torque
τ_{bst}	Boost time constant
$\tau_{bst,rising}$	Boost rising and falling time constant, respectively
$\tau_{bst,falling}$	
τ_{eng}	Final time constant
τ_{thr}	Time constant during throttle control
$f_{bst}(N)$	Boost torque speed line
N	Engine speed

Fuel Flow

To calculate the fuel economy for high-fidelity models, the block uses the volumetric fuel flow.

$$Q_{fuel} = \frac{\dot{m}_{fuel}}{\left(\frac{1000kg}{m^3}\right)Sg_{fuel}}$$

The equation uses these variables.

\dot{m}_{fuel}	Fuel mass flow
Sg_{fuel}	Specific gravity of fuel
Q_{fuel}	Volumetric fuel flow

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal	Description	Equations
PwrInflow	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrCrkshft Crankshaft power $-\tau_{eng}\omega$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrFuel Fuel input power $\dot{m}_{fuel}LHV$
		PwrLoss Power loss $\tau_{eng}\omega - \dot{m}_{fuel}LHV$
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	Not used	

The equations use these variables.

LHV	Fuel lower heating value
-------	--------------------------

ω	Engine speed, rad/s
\dot{m}_{fuel}	Fuel mass flow
τ_{eng}	Fuel mass per injection time constant

Ports

Input

TrqCmd – Commanded torque

scalar

Torque, T_{cmd} , in N·m.

EngSpd – Engine speed

scalar

Engine speed, N , in rpm.

EngTemp – Engine temperature

scalar

Engine temperature, $Temp_{Eng}$, in K.

Dependencies

To enable this port, select **Input engine temperature**.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
IntkGassMassFlw	Engine air mass flow output	kg/s
NrmlzdAirChrg	Normalized engine cylinder air mass	N/A
Afr	Air-fuel ratio (AFR)	N/A
FuelMassFlw	Engine fuel flow output	kg/s
FuelVolFlw	Volumetric fuel flow	m ³ /s
ExhManGasTemp	Engine exhaust gas temperature	K
EngTrq	Engine torque output	N·m
EngSpd	Engine speed	rpm

Signal		Description	Units	
CrkAng		Engine crankshaft absolute angle $\int_0^{(360)Cps} EngSpd \frac{180}{30} d\theta$ where <i>Cps</i> is crankshaft revolutions per power stroke.	degrees crank angle	
Bsfc		Engine brake-specific fuel consumption (BSFC)	g/kWh	
EoHC		Engine out hydrocarbon emission mass flow	kg/s	
EoCO		Engine out carbon monoxide emission mass flow rate	kg/s	
EoNOx		Engine out nitric oxide and nitrogen dioxide emissions mass flow	kg/s	
EoCO2		Engine out carbon dioxide emission mass flow	kg/s	
EoPM		Engine out particulate matter emission mass flow	kg/s	
PwrInfo	PwrTrnsfrd	PwrCrkshft	Crankshaft power	W
	PwrNotTrnsfrd	PwrFuel	Fuel input power	W
		PwrLoss	Power loss	W
	PwrStored		<i>Not used</i>	

EngTrq – Engine brake torque

scalar

Engine brake torque, T_{brake} , in N·m.**Parameters****Block Options****Include turbocharger lag effect – Increase time constant**

off (default)

To model turbocharger lag, select **Include turbocharger lag effect**. During throttle control, the time constant models the manifold filling and emptying dynamics. When the torque request requires a turbocharger boost, the block uses a larger time constant to represent the turbocharger lag. The block uses these equations.

Dynamic torque	$\frac{dT_{brake}}{dt} = \frac{1}{\tau_{eng}}(T_{stdy} - T_{brake})$
----------------	--

Boost time constant	$\tau_{bst} = \begin{cases} \tau_{bst, rising} & \text{when } T_{stdy} > T_{brake} \\ \tau_{bst, falling} & \text{when } T_{stdy} \leq T_{brake} \end{cases}$
Final time constant	$\tau_{eng} = \begin{cases} \tau_{thr} & \text{when } T_{brake} < f_{bst}(N) \\ \tau_{bst} & \text{when } T_{brake} \geq f_{bst}(N) \end{cases}$

The equations use these variables.

T_{brake}	Brake torque
T_{stdy}	Steady-state target torque
τ_{bst}	Boost time constant
$\tau_{bst, rising}$, $\tau_{bst, falling}$	Boost rising and falling time constant, respectively
τ_{eng}	Final time constant
τ_{thr}	Time constant during throttle control
$f_{bst}(N)$	Boost torque speed line
N	Engine speed

Dependencies

Selecting **Include turbocharger lag effect** enables these parameters:

- **Boost torque line, f_tbrake_bst**
- **Time constant below boost line, tau_thr**
- **Rising torque boost time constant, tau_bst_rising**
- **Falling torque boost time constant, tau_bst_falling**

Input engine temperature – Create input port

off (default) | on

Select this to create the EngTemp input port.

The block enables you to specify lookup tables for these engine characteristics. The lookup tables, developed with the Model-Based Calibration Toolbox, are functions of commanded torque, T_{cmd} , brake torque, T_{brake} , and engine speed, N . If you select **Input engine temperature**, the tables are also a function of engine temperature, $Temp_{Eng}$.

Table	Input Engine Temperature Parameter Setting	
	off	on
Power	$f(T_{cmd}, N)$	$f(T_{cmd}, N, Temp_{Eng})$
Air	$f(T_{brake}, N)$	$f(T_{brake}, N, Temp_{Eng})$
Fuel		
Temperature		
Efficiency		
HC		
CO		

Table	Input Engine Temperature Parameter Setting	
	off	on
NOx		
CO2		
PM		

Configuration

Calibrate Maps – Calibrate tables with measured data selection

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the 2D lookup tables using measured data. The dialog box steps through these tasks.

Task	Description				
Import firing data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/mbc/mbctraining/SiEngineData.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <table border="1"> <thead> <tr> <th>Required Data</th> <th>Optional Data</th> </tr> </thead> <tbody> <tr> <td> <ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m </td> <td> <ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s </td> </tr> </tbody> </table> <p>Collect firing data at steady-state operating conditions when injectors deliver the fuel. Data should cover the engine speed and torque operating range. Model-Based Calibration Toolbox uses the firing data boundary as the maximum torque.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Required Data	Optional Data	<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s
Required Data	Optional Data				
<ul style="list-style-type: none"> Engine speed, rpm Engine torque, N·m 	<ul style="list-style-type: none"> Air mass flow rate, kg/s Brake specific fuel consumption, g/(kW·h) CO2 mass flow rate, kg/s CO mass flow rate, kg/s Exhaust temperature, K Fuel mass flow rate, kg/s HC mass flow rate, kg/s NOx mass flow rate, kg/s Particulate matter mass flow rate, kg/s 				

Task	Description
Import non-firing data	<p>Import this non-firing data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autodemos/projectsrc/SIDynamometer/CalMappedEng/SiEngineData.xlsx</code>.</p> <ul style="list-style-type: none"> • Engine speed, rpm • Engine torque, N·m <p>Collect non-firing (motoring) data at steady-state operating conditions when fuel is cut off. All non-firing torque points must be less than zero. Non-firing data is a function of engine speed only.</p>
Generate response models	<p>For both firing and non-firing data, the Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>
Generate calibration	<p>Model-Based Calibration Toolbox calibrates the firing and non-firing response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>
Update block parameters	<p>Update the block lookup table and breakpoint parameters with the calibration.</p>

Dependencies

To enable this parameter, clear **Input engine temperature**.

Breakpoints for commanded torque, f_tbrake_t_bpt – Breakpoints

1-by-M vector

Breakpoints, in N·m.

Breakpoints for engine speed input, f_tbrake_n_bpt – Breakpoints

1-by-N vector

Breakpoints, in rpm.

Breakpoints for temperature input, f_tbrake_engtmp_bpt – Breakpoints

[233.15 273.15 373.15] (default) | 1-by-L vector

Breakpoints, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

Number of cylinders, NCyl – Number

4 (default) | scalar

Number of cylinders.

Crank revolutions per power stroke, Cps – Crank revolutions

2 (default) | scalar

Crank revolutions per power stroke.

Total displaced volume, Vd – Volume

0.0015 (default) | scalar

Volume displaced by engine, in m^3 .**Fuel lower heating value, Lhv – Heating value**

45e6 (default) | scalar

Fuel lower heating value, LHV , in J/kg.**Fuel specific gravity, Sg – Specific gravity**

0.745 (default) | scalar

Specific gravity of fuel, Sg_{fuel} , dimensionless.**Ideal gas constant air, Rair – Constant**

287 (default) | scalar

Ideal gas constant of air and residual gas entering the engine intake port, in J/(kg*K).

Air standard pressure, Pstd – Pressure

101325 (default) | scalar

Standard air pressure, in Pa.

Air standard temperature, Tstd – Temperature

293.15 (default) | scalar

Standard air temperature, in K.

Boost torque line, f_tbrake_bst – Boost lag

1-by-M vector

Boost torque line, $f_{bst}(N)$, in N·m.**Dependencies**To enable this parameter, select **Include turbocharger lag effect**.**Time constant below boost line – Time constant below**

0.2 (default) | scalar

Time constant below boost line, τ_{thr} , in s.**Dependencies**To enable this parameter, select **Include turbocharger lag effect**.**Rising torque boost time constant, tau_bst_rising – Rising time constant**

1.5 (default) | scalar

Rising torque boost time constant, $\tau_{bst,rising}$, in s.

Dependencies

To enable this parameter, select **Include turbocharger lag effect**.

Falling torque boost time constant, tau_bst_falling — Falling time constant
1 (default) | scalar

Falling torque boost time constant, $\tau_{bst,falling}$, in s.

Dependencies

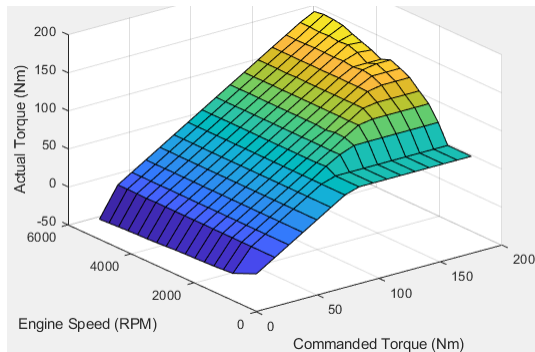
To enable this parameter, select **Include turbocharger lag effect**.

Power

Brake torque map, f_tbrake — 2D lookup table
M-by-N matrix

The engine torque lookup table is a function of commanded engine torque and engine speed, $T = f(T_{cmd}, N)$, where:

- T is engine torque, in N·m.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Plot brake torque map — Plot table
button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Brake torque map, f_tbrake_3d — 3D lookup table
M-by-N-by-L array

The engine torque lookup table is a function of commanded engine torque, engine speed, and engine temperature, $T = f(T_{cmd}, N, Temp_{Eng})$, where:

- T is engine torque, in N·m.
- T_{cmd} is commanded engine torque, in N·m.

- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

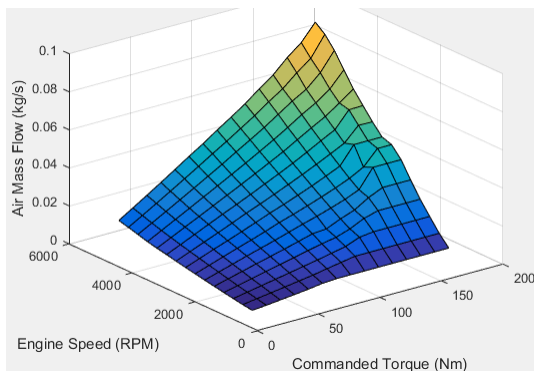
Air

Air mass flow map, f_{air} – 2D lookup table

M-by-N matrix

The engine air mass flow lookup table is a function of commanded engine torque and engine speed, $\dot{m}_{intk} = f(T_{cmd}, N)$, where:

- \dot{m}_{intk} is engine air mass flow, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot air mass map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Air mass flow map, f_{air_3d} – 3D lookup table

M-by-N-by-L array

The engine air mass flow lookup table is a function of commanded engine torque, engine speed, and engine temperature, $\dot{m}_{intk} = f(T_{cmd}, N, Temp_{Eng})$, where:

- \dot{m}_{intk} is engine air mass flow, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.

- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

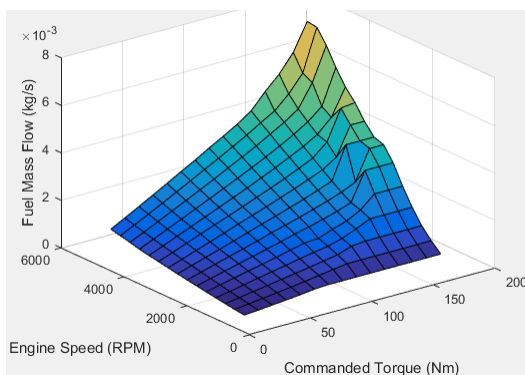
Fuel

Fuel flow map, f_fuel – 2D lookup table

M-by-N matrix

The engine fuel mass flow lookup table is a function of commanded engine torque and engine speed, $MassFlow = f(T_{cmd}, N)$, where:

- $MassFlow$ is engine fuel mass flow, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot fuel flow map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Fuel flow map, f_fuel_3d – 3D lookup table

M-by-N-by-L array

The engine fuel mass flow lookup table is a function of commanded engine torque, engine speed, and engine temperature, $MassFlow = f(T_{cmd}, N, Temp_{Eng})$, where:

- $MassFlow$ is engine fuel mass flow, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

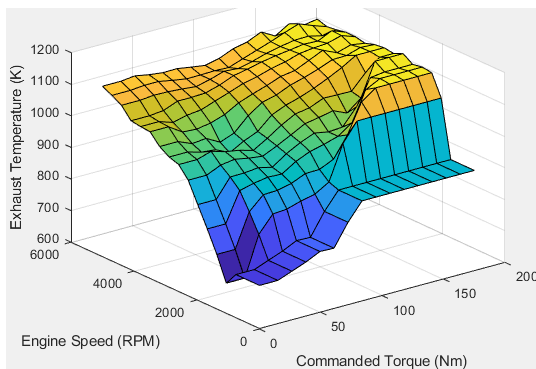
Temperature

Exhaust temperature map, f_{texh} – 2D lookup table

M-by-N matrix

The engine exhaust temperature lookup table is a function of commanded engine torque and engine speed, $T_{exh} = f(T_{cmd}, N)$, where:

- T_{exh} is exhaust temperature, in K.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot exhaust temperature map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Exhaust temperature map, f_{texh_3d} – 3D lookup table

array

The engine exhaust temperature lookup table is a function of commanded engine torque, engine speed, and engine temperature, $T_{exh} = f(T_{cmd}, N, Temp_{Eng})$, where:

- T_{exh} is exhaust temperature, in K.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

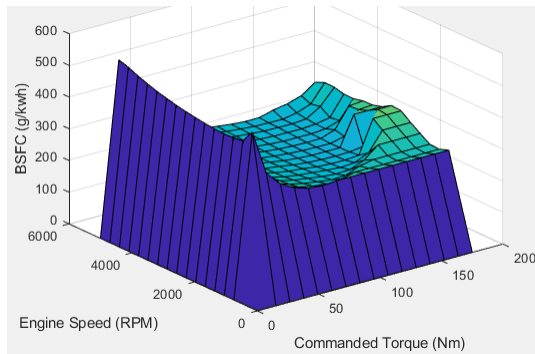
Efficiency

BSFC map, f_eff — 2D lookup table

M-by-N-by-L array

The brake-specific fuel consumption (BSFC) efficiency is a function of commanded engine torque and engine speed, $BSFC = f(T_{cmd}, N)$, where:

- $BSFC$ is BSFC, in g/kWh.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot BSFC map — Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

BSFC map, f_eff_3d — 3D lookup table

M-by-N-by-L array

The brake-specific fuel consumption (BSFC) efficiency is a function of commanded engine torque, engine speed, and engine temperature, $BSFC = f(T_{cmd}, N, Temp_{Eng})$, where:

- $BSFC$ is BSFC, in g/kWh.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

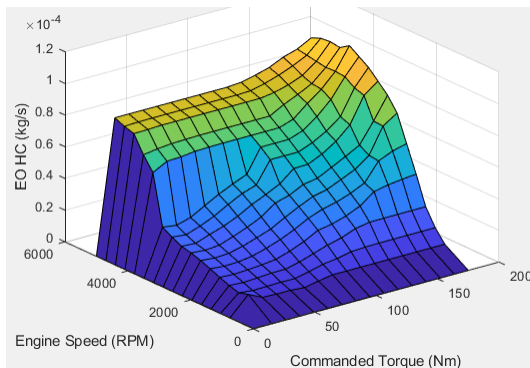
To enable this parameter, select **Input engine temperature**.

HC**E0 HC map, f_hc – 2D lookup table**

M-by-N matrix

The engine-out hydrocarbon emissions are a function of commanded engine torque and engine speed, $EO\ HC = f(T_{cmd}, N)$, where:

- $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

**Dependencies**

To enable this parameter, clear **Input engine temperature**.

Plot E0 HC map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 HC map, f_hc_3d – 3D lookup table

M-by-N-by-L array

The engine-out hydrocarbon emissions are a function of commanded engine torque, engine speed, and engine temperature, $EO\ HC = f(T_{cmd}, N, Temp_{Eng})$, where:

- $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

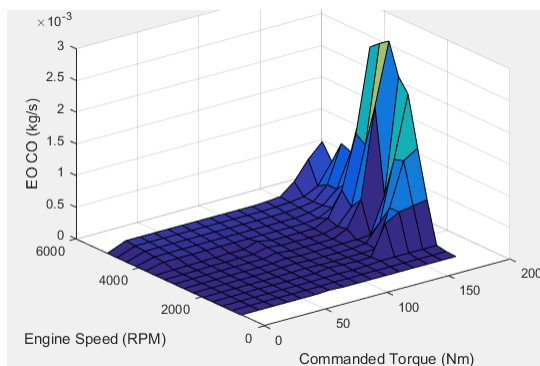
To enable this parameter, select **Input engine temperature**.

CO**E0 CO map, f_co – 2D lookup table**

M-by-N matrix

The engine-out carbon monoxide emissions are a function of commanded engine torque and engine speed, $EO\ CO = f(T_{cmd}, N)$, where:

- $EO\ CO$ is engine-out carbon monoxide emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

**Dependencies**

To enable this parameter, clear **Input engine temperature**.

Plot E0 CO map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 HC map, f_hc_3d – 3D lookup table

M-by-N-by-L array

The engine-out hydrocarbon emissions are a function of commanded engine torque, engine speed, and engine temperature, $EO\ HC = f(T_{cmd}, N, Temp_{Eng})$, where:

- $EO\ HC$ is engine-out hydrocarbon emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

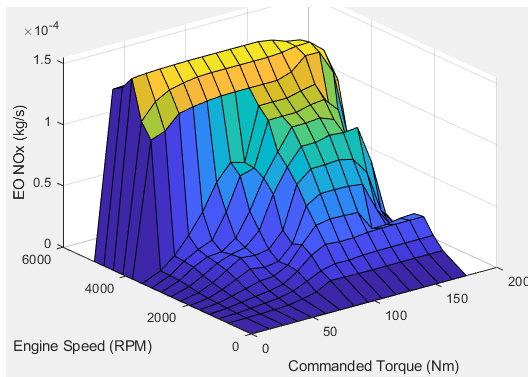
To enable this parameter, select **Input engine temperature**.

NOx**E0 NOx map, f_nox – 2D lookup table**

M-by-N matrix

The engine-out nitric oxide and nitrogen dioxide emissions are a function of commanded engine torque and engine speed, $EO\ NOx = f(T_{cmd}, N)$, where:

- $EO\ NOx$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

**Dependencies**

To enable this parameter, clear **Input engine temperature**.

Plot E0 NOx map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 NOx map, f_nox_3d – 3D lookup table

M-by-N-by-L array

The engine-out nitric oxide and nitrogen dioxide emissions are a function of commanded engine torque, engine speed, and engine temperature, $EO\ NOx = f(T_{cmd}, N, Temp_{Eng})$, where:

- $EO\ NOx$ is engine-out nitric oxide and nitrogen dioxide emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

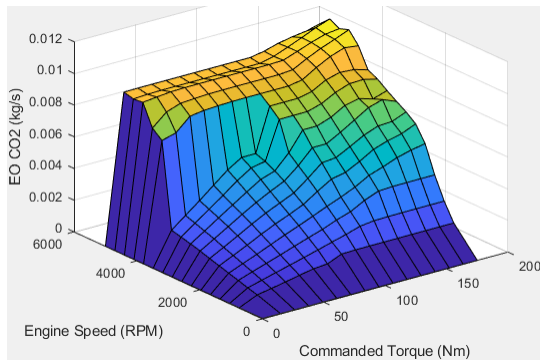
CO2

E0 CO2 map, f_co2 – 2D lookup table

M-by-N matrix

The engine-out carbon dioxide emissions are a function of commanded engine torque and engine speed, $EO\ CO2 = f(T_{cmd}, N)$, where:

- $EO\ CO2$ is engine-out carbon dioxide emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.



Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot CO2 map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 CO2 map, f_co2_3d – 3D lookup table

M-by-N-by-L array

The engine-out carbon dioxide emissions are a function of commanded engine torque, engine speed, and engine temperature, $EO\ CO2 = f(T_{cmd}, N, Temp_{Eng})$, where:

- $EO\ CO2$ is engine-out carbon dioxide emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

PM**E0 PM map, f_pm – 2D lookup table**

M-by-N matrix

The engine-out particulate matter emissions are a function of commanded engine torque and engine speed, where:

- $EO\ PM$ is engine-out PM emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.

Dependencies

To enable this parameter, clear **Input engine temperature**.

Plot E0 PM map – Plot table

button

Click to plot table.

Dependencies

To enable this parameter, clear **Input engine temperature**.

E0 PM map, f_pm_3d – 3D lookup table

M-by-N-by-L array

The engine-out particulate matter emissions are a function of commanded engine torque, engine speed, and engine temperature, where:

- $EO\ PM$ is engine-out PM emissions, in kg/s.
- T_{cmd} is commanded engine torque, in N·m.
- N is engine speed, in rpm.
- $Temp_{Eng}$ is engine temperature, in K.

Dependencies

To enable this parameter, select **Input engine temperature**.

Version History

Introduced in R2017a

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

See Also

SI Core Engine | Mapped Motor | Mapped CI Engine

Topics

“Generate Mapped SI Engine from a Spreadsheet”

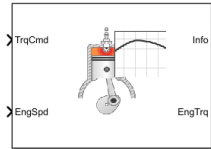
“Engine Calibration Maps”

“Model-Based Calibration Toolbox”

Simple Engine

Simplified engine model using lookup tables

Library: Powertrain Blockset / Propulsion / Combustion Engines
Vehicle Dynamics Blockset / Powertrain / Propulsion



Description

The Simple Engine block implements a simplified engine model using a maximum torque vs engine speed table, two scalar fuel mass properties, and one scalar engine efficiency parameter to estimate engine torque and fuel flow. You can use the block for:

- Hardware-in-the-loop (HIL) engine control design
- Vehicle-level fuel economy and performance simulations

Ports

Input

TrqCmd — Commanded torque

scalar

Torque, in N·m.

EngSpd — Engine speed

scalar

Engine speed, in rpm.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
IntkGasMassFlw (zeroed out intentionally)	Engine air mass flow output	kg/s
NrmLzdAirChrg (zeroed out intentionally)	Normalized engine cylinder air mass	N/A
Afr (zeroed out intentionally)	Air-fuel ratio (AFR)	N/A
FuelMassFlw	Engine fuel flow output	kg/s
FuelVolFlw	Volumetric fuel flow	m ³ /s
ExhManGasTemp (zeroed out intentionally)	Engine exhaust gas temperature	K

Signal		Description	Units	
EngTrq		Engine torque output	N·m	
EngSpd		Engine speed	rpm	
CrkAng (zeroed out intentionally)		Engine crankshaft absolute angle $\int_0^{(360)Cps} EngSpd \frac{180}{30} d\theta$ where <i>Cps</i> is crankshaft revolutions per power stroke.	degrees crank angle	
Bsfc		Engine brake-specific fuel consumption (BSFC)	g/kWh	
EoHC (zeroed out intentionally)		Engine out hydrocarbon emission mass flow	kg/s	
EoCO (zeroed out intentionally)		Engine out carbon monoxide emission mass flow rate	kg/s	
EoNOx (zeroed out intentionally)		Engine out nitric oxide and nitrogen dioxide emissions mass flow	kg/s	
EoCO2 (zeroed out intentionally)		Engine out carbon dioxide emission mass flow	kg/s	
EoPM (zeroed out intentionally)		Engine out particulate matter emission mass flow	kg/s	
PwrInfo	PwrTrnsfrd	PwrCrkshft	Crankshaft power	W
	PwrNotTrnsfrd	PwrFuel	Fuel input power	W
		PwrLoss	Power loss	W
	PwrStored		<i>Not used</i>	

EngTrq – Engine brake torque
scalar

Engine brake torque, in N·m.

Parameters

Engine maximum torque, f_tqmax – Breakpoints

[75.679776480773256 75.679776480773256 97.173658538143172 116.84042599160529 152.21029882684542 175 174.99889520597083 174.99996520122858 175 175 175 175 175 175 175] (default)

Breakpoints, in N·m.

Breakpoints for engine speed input, f_tqmax_n_bpt – Breakpoints

[0 750 1053.57142857143 1357.14285714286 1660.71428571429 1964.28571428571 2267.85714285714 2571.42857142857 2875 3178.57142857143 3482.14285714286 3785.71428571429 4089.28571428571 4392.85714285714 4696.42857142857 5000] (default)

Breakpoints, in rpm.

Fuel lower heating value, Lhv — Heating value

4.6E+7 (default)

Fuel lower heating value, in J/kg.

Fuel specific gravity, Sg — Specific gravity

0.745 (default)

Specific gravity of fuel, dimensionless.

Average brake specific fuel consumption, BsfcAvg — Average brake specific fuel consumption

350 (default)

Average brake specific fuel consumption, in g/kwh.

Version History

Introduced in R2021b

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

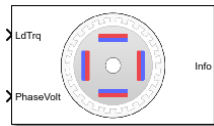
See Also

Electric Motor, Converters, Inverter Blocks

Interior PMSM

Three-phase interior permanent magnet synchronous motor with sinusoidal back electromotive force

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters
Motor Control Blockset / Electrical Systems / Motors



Description

The Interior PMSM block implements a three-phase interior permanent magnet synchronous motor (PMSM) with sinusoidal back electromotive force. The block uses the three-phase input voltages to regulate the individual phase currents, allowing control of the motor torque or speed.

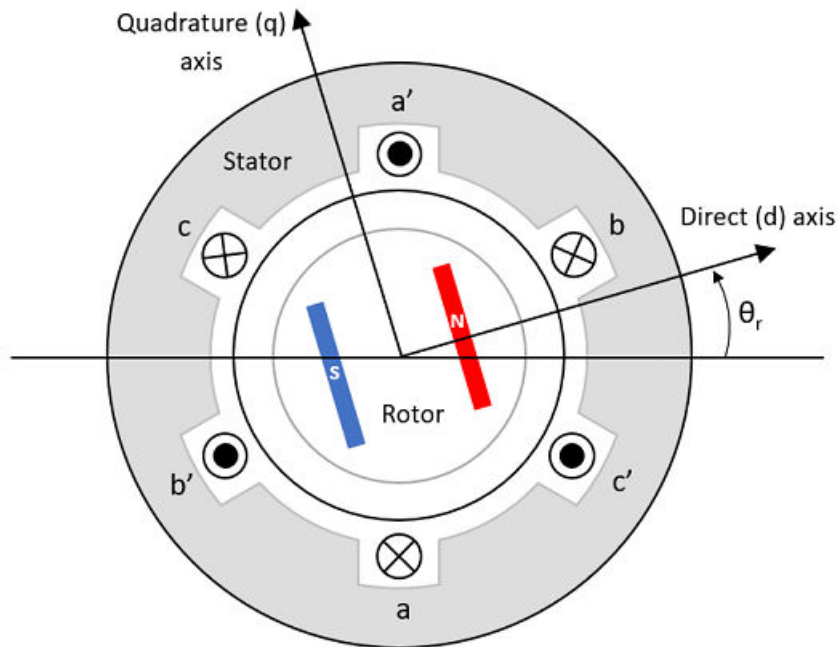
By default, the block sets the **Simulation type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

On the **Parameters** tab, if you select **Back-emf**, the block implements this equation to calculate the permanent flux linkage constant.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Motor Construction

This figure shows the motor construction with a single pole pair on the motor.



The motor magnetic field due to the permanent magnets creates a sinusoidal rate of change of flux with motor angle.

For the axes convention, the a -phase and permanent magnet fluxes are aligned when motor angle θ_r is zero.

Three-Phase Sinusoidal Model Electrical System

The block implements these equations, expressed in the motor flux reference frame (dq frame). All quantities in the motor reference frame are referred to the stator.

$$\omega_e = P\omega_m$$

$$\frac{d}{dt}i_d = \frac{1}{L_d}v_d - \frac{R}{L_d}i_d + \frac{L_q}{L_d}P\omega_m i_q$$

$$\frac{d}{dt}i_q = \frac{1}{L_q}v_q - \frac{R}{L_q}i_q - \frac{L_d}{L_q}P\omega_m i_d - \frac{\lambda_{pm}P\omega_m}{L_q}$$

$$T_e = 1.5P[\lambda_{pm}i_q + (L_d - L_q)i_d i_q]$$

The L_q and L_d inductances represent the relation between the phase inductance and the motor position due to the saliency of the motor.

The equations use these variables.

L_q, L_d	q- and d-axis inductances (H)
R	Resistance of the stator windings (ohm)
i_q, i_d	q- and d-axis currents (A)
v_q, v_d	q- and d-axis voltages (V)

ω_m	Angular mechanical velocity of the motor (rad/s)
ω_e	Angular electrical velocity of the motor (rad/s)
λ_{pm}	Permanent flux linkage constant (Wb)
K_e	Back electromotive force (EMF) (Vpk_LL/krpm, where Vpk_LL is the peak voltage line-to-line measurement)
P	Number of pole pairs
T_e	Electromagnetic torque (Nm)
θ_e	Electrical angle (rad)

Mechanical System

The motor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of motor and load (kgm ²)
F	Combined viscous friction of motor and load (N·m/(rad/s))
θ_m	Motor mechanical angular position (rad)
T_m	Motor shaft torque (Nm)
T_e	Electromagnetic torque (Nm)
T_f	Motor shaft static friction torque (Nm)
ω_m	Angular mechanical velocity of the motor (rad/s)

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	$P_{bus} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	$P_{elec} = -\frac{3}{2}(R_{s1}i_{sd}^2 + R_{s1}i_{sq}^2)$
	<ul style="list-style-type: none"> Positive signals indicate an input 			

Bus Signal		Description	Variable	Equations
	<ul style="list-style-type: none"> Negative signals indicate a loss 	PwrMech Loss	Mechanical power loss	P_{mech} When Port Configuration is set to Torque: $P_{mech} = -(\omega_m^2 F + \omega_m T_f)$ When Port Configuration is set to Speed: $P_{mech} = 0$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrMtrStored	Stored motor power	$P_{str} = \frac{P_{bus}}{P_{elec}} + \frac{P_{mot}}{P_{mech}}$

The equations use these variables.

R_s	Stator resistance (ohm)
i_a, i_b, i_c	Stator phase a, b, and c current (A)
i_{sq}, i_{sd}	Stator q- and d-axis currents (A)
v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage (V)
ω_m	Angular mechanical velocity of the rotor (rad/s)
F	Combined motor and load viscous damping (N·m/(rad/s))
T_e	Electromagnetic torque (Nm)
T_f	Combined motor and load friction torque (Nm)

Amplitude invariant dq transformation

The block uses these equations to implement amplitude invariant dq transformation to ensure that the dq and three phase amplitudes are equal.

$$\begin{bmatrix} v_{sd} \\ v_{sq} \end{bmatrix} = \frac{2}{3} \begin{bmatrix} \cos(\theta_{da}) & \cos(\theta_{da} - \frac{2\pi}{3}) & \cos(\theta_{da} + \frac{2\pi}{3}) \\ -\sin(\theta_{da}) & -\sin(\theta_{da} - \frac{2\pi}{3}) & -\sin(\theta_{da} + \frac{2\pi}{3}) \end{bmatrix} \begin{bmatrix} v_a \\ v_b \\ v_c \end{bmatrix}$$

$$\begin{bmatrix} i_a \\ i_b \\ i_c \end{bmatrix} = \begin{bmatrix} \cos(\theta_{da}) & -\sin(\theta_{da}) \\ \cos(\theta_{da} - \frac{2\pi}{3}) & -\sin(\theta_{da} - \frac{2\pi}{3}) \\ \cos(\theta_{da} + \frac{2\pi}{3}) & -\sin(\theta_{da} + \frac{2\pi}{3}) \end{bmatrix} \begin{bmatrix} i_{sd} \\ i_{sq} \end{bmatrix}$$

The equations use these variables.

θ_{da}	dq stator electrical angle with respect to the rotor a -axis (rad)
v_{sq}, v_{sd}	Stator q - and d -axis voltages (V)
i_{sq}, i_{sd}	Stator q - and d -axis currents (A)
v_a, v_b, v_c	Stator voltage phases a, b, c (V)
i_a, i_b, i_c	Stator currents phases a, b, c (A)

Ports

Input

LdTrq – Load torque on motor

scalar

Load torque on the motor shaft, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port Configuration** parameter.

Spd – Motor shaft speed

scalar

Angular velocity of the motor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port Configuration** parameter.

PhaseVolt – Stator terminal voltages

1-by-3 array

Stator terminal voltages, $V_a, V_b,$ and V_c , in V.

Dependencies

To create this port, select Speed or Torque for the **Port Configuration** parameter.

Output

Info – Bus signal

bus

The bus signal contains these block calculations.

Signal	Description	Variable	Units
IaStator	Stator phase current A	i_a	A
IbStator	Stator phase current B	i_b	A
IcStator	Stator phase current C	i_c	A
IdSync	Direct axis current	i_d	A
IqSync	Quadrature axis current	i_q	A
VdSync	Direct axis voltage	v_d	V

Signal		Description	Variable	Units	
VqSync		Quadrature axis voltage	v_q	V	
MtrSpd		Angular mechanical velocity of the motor	ω_m	rad/s	
MtrPos		Motor mechanical angular position	θ_m	rad	
MtrTrq		Electromagnetic torque	T_e	N·m	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr — Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq — Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Mechanical input configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Mechanical input configuration** parameter.

Parameters

Block Options

Mechanical input configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd

Port Configuration	Creates Input Port	Creates Output Port
Speed	Spd	MtrTrq

Simulation type – Select simulation type

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to Discrete.

Dependencies

Setting **Simulation type** to Discrete creates the **Sample Time, Ts** parameter.

Sample Time (Ts) – Sample time for discrete integration

0.001 (default) | scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation type** to Discrete creates the **Sample Time, Ts** parameter.

Parameters**Number of pole pairs (P) – Pole pairs**

4 (default) | scalar

Motor pole pairs, P .

Stator phase resistance per phase (Rs) – Resistance

.2 (default) | scalar

Stator phase resistance per phase, R_s , in ohm.

Stator d-axis and q-axis inductance (Ldq) – Inductance

[3.752e-4 4.148e-4] (default) | vector

Stator d-axis and q-axis inductance, L_d , L_q , in H.

Permanent flux linkage constant (lambda_pm) – Flux

0.1194 (default) | scalar

Permanent flux linkage constant, λ_{pm} , in Wb.

Back-emf constant (Ke) – Back electromotive force

scalar

Back electromotive force, EMF, K_e , in Vpk_LL/krpm. Vpk_LL is the peak voltage line-to-line measurement.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Physical inertia, viscous damping, and static friction (mechanical) — Inertia, damping, friction

[0.002700, 4.924e-4, 0] (default) | vector

Mechanical properties of the motor:

- Inertia, J , in $\text{kg}\cdot\text{m}^2$
- Viscous damping, F , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction, T_f , in $\text{N}\cdot\text{m}$

Dependencies

To enable this parameter, select the Torque configuration parameter.

Initial Values**Initial d-axis and q-axis current (idq0) — Current**

[0 0] (default) | vector

Initial q- and d-axis currents, i_q , i_d , in A.**Initial mechanical position (theta_init) — Angle**

0 (default) | scalar

Initial motor angular position, θ_{m0} , in rad.**Initial mechanical speed (omega_init) — Speed**

0 (default) | scalar

Initial angular velocity of the motor, ω_{m0} , in rad/s.**Dependencies**

To enable this parameter, select the Torque configuration parameter.

Version History

Introduced in R2017a

References

- [1] Kundur, P. *Power System Stability and Control*. New York, NY: McGraw Hill, 1993.
- [2] Anderson, P. M. *Analysis of Faulted Power Systems*. Hoboken, NJ: Wiley-IEEE Press, 1995.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Interior PM Controller | Flux-Based PMSM | Induction Motor | Mapped Motor | Surface Mount PMSM

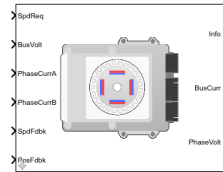
Topics

“Estimate Motor Parameters Using Motor Control Blockset Parameter Estimation Tool” (Motor Control Blockset)

Interior PM Controller

Torque-based, field-oriented controller for an internal permanent magnet synchronous motor

Library: Powertrain Blockset / Propulsion / Electric Motor Controllers

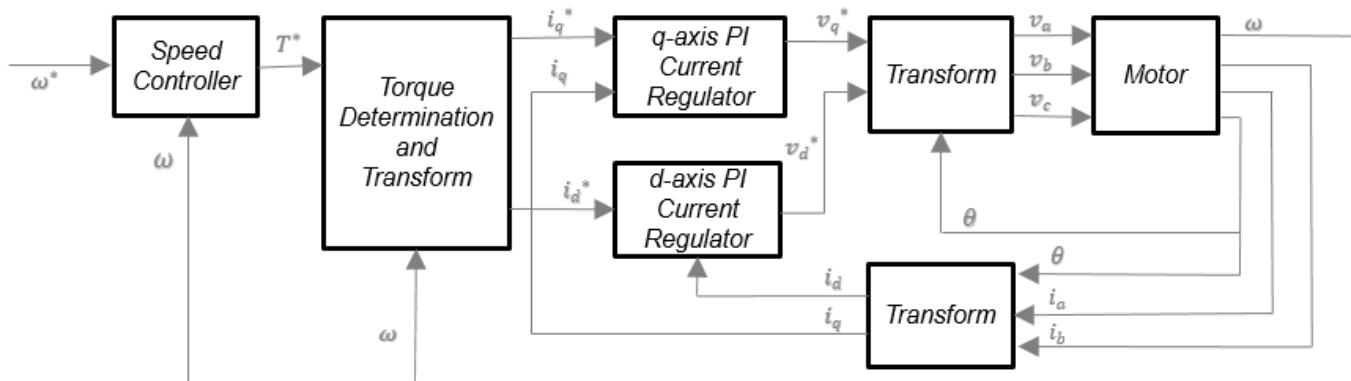


Description

The Interior PM Controller block implements a torque-based, field-oriented controller for an internal permanent magnet synchronous motor (PMSM) with an optional outer-loop speed controller. The internal torque control implements strategies for achieving maximum torque per ampere (MTPA) and weakening the magnetic flux. You can specify either the speed or torque control type.

The Interior PM Controller implements equations for speed control, torque determination, regulators, transforms, and motors.

The figure illustrates the information flow in the block.



The block implements equations that use these variables.

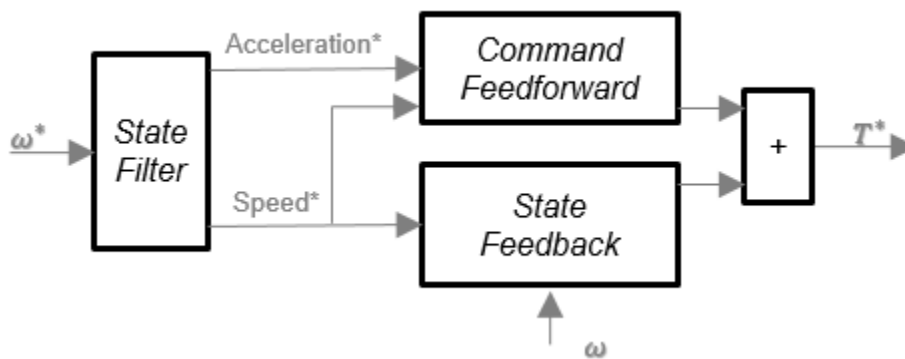
ω	Rotor speed
ω^*	Rotor speed command
T^*	Torque command
i_d	d-axis current
i_d^*	d-axis current command
i_q	q-axis current
i_q^*	q-axis current command

v_d	d-axis voltage
v_d^*	d-axis voltage command
v_q	q-axis voltage
v_q^*	q-axis voltage command
v_a, v_b, v_c	Stator phase a, b, c voltages
i_a, i_b, i_c	Stator phase a, b, c currents

Speed Controller

To implement the speed controller, select the **Control Type** parameter `Speed Control`. If you select the **Control Type** parameter `Torque Control`, the block does not implement the speed controller.

The speed controller determines the torque command by implementing a state filter, and calculating the feedforward and feedback commands. If you do not implement the speed controller, input a torque command to the Interior PM Controller block.



State Filter

The state filter is a low-pass filter that generates the acceleration command based on the speed command. On the **Speed Controller** tab:

- To make the speed-command lag time negligible, specify a **Bandwidth of the state filter** parameter.
- To calculate a **Speed regulation time constant, Ksf** gain based on the state filter bandwidth, select **Calculate Speed Regulator Gains**.

The discrete form of characteristic equation is given by:

$$z + K_{sf}T_{sm} - 1$$

The filter calculates the gain using this equation.

$$K_{sf} = \frac{1 - \exp(-T_{sm}2\pi EV_{sf})}{T_{sm}}$$

The equations use these variables.

EV_{sf}	Bandwidth of the speed command filter
T_{sm}	Motion controller sample time
K_{sf}	Speed regulator time constant

State Feedback

To generate the state feedback torque, the block uses the filtered speed error signal from the state filter. The feedback torque calculation also requires gains for speed regulator.

On the **Speed Controller** tab, select **Calculate Speed Regulator Gains** to calculate:

- **Proportional gain, b_a**
- **Angular gain, K_{sa}**
- **Rotational gain, K_{isa}**

For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value on the **Motor Parameters** tab.

The gains for the state feedback are calculated using these equations.

Calculation	Equations
Discrete forms of characteristic equation	$z^3 + \frac{(-3J_p + T_s b_a + T_s^2 K_{sa} + T_s^3 K_{isa})}{J_p} z^2 + \frac{(3J_p - 2T_s b_a - T_s^2 K_{sa})}{J_p} z + \frac{-J_p + T_s b_a}{J_p}$ $(z - p_1)(z - p_2)(z - p_3) = z^3 + (p_1 + p_2 + p_3)z^2 + (p_1 p_2 + p_2 p_3 + p_1 p_3)z^2 - p_1 p_2 p_3$
Speed regulator proportional gain	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$
Speed regulator integral gain	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$
Speed regulator double integral gain	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
J_p	Motor inertia
T_{sm}	Motion controller sample time

Command Feedforward

To generate the state feedforward torque, the block uses the filtered speed and acceleration from the state filter. Also, the feedforward torque calculation uses the inertia, viscous damping, and static friction. To achieve zero tracking error, the torque command is the sum of the feedforward and feedback torque commands.

Selecting **Calculate Speed Regulator Gains** on the **Speed Controller** tab updates the inertia, viscous damping, and static friction with the **Physical inertia, viscous damping, static friction** parameter values on the **Motor Parameters** tab.

The feedforward torque command uses this equation.

$$T_{cmd_ff} = J_p \dot{\omega}_m + F_v \omega_m + F_s \frac{\omega_m}{|\omega_m|}$$

where:

J_p	Motor inertia
T_{cmd_ff}	Torque command feedforward
F_s	Static friction torque constant
F_v	Viscous friction torque constant
F_s	Static friction torque constant
ω_m	Rotor speed

Torque Determination

The block uses a maximum torque per ampere (MTPA) trajectory to calculate the base speed and the current commands. The available bus voltage determines the base speed. The direct (d) and quadrature (q) permanent magnet (PM) determines the induced voltage.

Calculation	Equations
Electrical base speed transition into field weakening	$\omega_{base} = \frac{v_{max}}{\sqrt{(L_q i_q)^2 + (L_d i_d + \lambda_{pm})^2}}$
d-axis voltage	$v_d = -\omega_e L_q i_{q_{max}}$
q-axis voltage	$v_q = \omega_e (L_d i_{d_{max}} + \lambda_{pm})$
Maximum phase current	$i_{max}^2 = i_{d_{max}}^2 + i_{q_{max}}^2$
Maximum line to neutral voltage	$v_{max} = \frac{v_{bus}}{\sqrt{3}}$
d-axis phase current MTPA table	$I_m = \frac{2T_{max}}{3P\lambda_{pm}}$ $i_{d_mtpa} = \frac{\lambda_{pm}}{4(L_q - L_d)} - \sqrt{\frac{\lambda_{pm}^2}{16(L_q - L_d)^2} + \frac{I_m^2}{2}}$
q-axis phase current MTPA table	$i_{q_mtpa} = \sqrt{I_m^2 - (i_{mtpa})^2}$
Torque MTPA breakpoints	$T_{mtpa} = \frac{3}{2}P(\lambda_{pm} i_q + (L_d - L_q) i_d i_q)$

Calculation	Equations
Field weakening, using the speed-based voltage limits	$(L_q i_q)^2 + (L_d i_d + \lambda_{pm})^2 \leq \frac{v_{max}^2}{\omega_e^2}$ $i_q = \sqrt{i_{max}^2 - i_d^2}$ $(L_d^2 - L_q^2) i_d^2 + 2\lambda_{pm} L_d i_d + \lambda_{pm}^2 + L_q^2 i_{max}^2 - \frac{v_{max}^2}{\omega_e^2} = 0$ $i_{dfw} = \frac{-\lambda_{pm} L_d + \sqrt{(\lambda_{pm} L_d)^2 - (L_d^2 - L_q^2) \left(\lambda_{pm}^2 + L_q^2 i_{max}^2 - \frac{v_{max}^2}{\omega_e^2} \right)}}{(L_d^2 - L_q^2)}$ $T_{fw} = \frac{3}{2} P (\lambda_{pm} i_{qfw} + (L_d - L_q) i_{dfw} i_{qfw})$
Current command	<p>If $\omega_e \leq \omega_{base}$</p> $i_{dref} = i_{dmtpa}(T_{ref})$ $i_{qref} = i_{qmtpa}(T_{ref})$ <p>Else</p> $i_{dfw} = \max(i_{dfw}, -i_{max})$ $i_{qfw} = \sqrt{i_{max}^2 - i_d^2}$ <p>If $T_{fw} < T_{ref}$</p> $i_{dref} = i_{dfw}$ $i_{qref} = i_{qfw}$ <p>Else</p> $i_{dref} = i_{dfw}$ $i_{qref} = \frac{T_{ref}}{\frac{3}{2} P (\lambda_{pm} + (L_d - L_q) i_{dfw})}$ <p>End</p> <p>End</p>

The equations use these variables.

i_{max}	Maximum phase current
i_d	d-axis current
i_q	q-axis current
i_{d_max}	Maximum d-axis phase current
i_{q_max}	Maximum q-axis phase current
i_{d_mtpa}	d-axis phase current MTPA table
i_{q_mtpa}	q-axis phase current MTPA table
I_m	Estimated maximum current
i_{dfw}	d-axis field weakening current
i_{qfw}	q-axis field weakening current

ω_e	Rotor electrical speed
λ_{pm}	Permanent magnet flux linkage
v_d	d-axis voltage
v_q	q-axis voltage
v_{max}	Maximum line to neutral voltage
v_{bus}	DC bus voltage
L_d	d-axis winding inductance
L_q	q-axis winding inductance
P	Motor pole pairs
T_{fw}	Field weakening torque
T_{mtpa}	Torque MTPA breakpoints

Current Regulators

The block regulates the current with an anti-windup feature. Classic proportional-integrator (PI) current regulators do not consider the d-axis and q-axis coupling or the back-electromagnetic force (EMF) coupling. As a result, transient performance deteriorates. To account for the coupling, the block implements the complex vector current regulator (CVCR) in the scalar format of the rotor reference frame. The CVCR decouples:

- d-axis and q-axis current cross-coupling
- Back-EMF cross-coupling

The current frequency response is a first-order system, with a bandwidth of $EV_{current}$.

The block implements these equations.

Calculation	Equations
Motor voltage, in the rotor reference frame	$L_d \frac{di_d}{dt} = v_d - R_s i_d + p\omega_m L_q i_q$ $L_q \frac{di_q}{dt} = v_q - R_s i_q - p\omega_m L_d i_d - p\omega_m \lambda_{pm}$
Current regulator gains	$\omega_b = 2\pi EV_{current}$ $K_{p_d} = L_d \omega_b$ $K_{p_q} = L_q \omega_b$ $K_i = R_s \omega_b$
Transfer functions	$\frac{i_d}{i_{dref}} = \frac{\omega_b}{s + \omega_b}$ $\frac{i_q}{i_{qref}} = \frac{\omega_b}{s + \omega_b}$

The equations use these variables.

$EV_{current}$	Current regulator bandwidth
i_d	d-axis current

i_q	q-axis current
$K_{p,d}$	Current regulator d-axis gain
$K_{p,q}$	Current regulator q-axis gain
L_d	d-axis winding inductance
L_q	q-axis winding inductance
R_s	Stator phase winding resistance
ω_m	Rotor speed
v_d	d-axis voltage
v_q	q-axis voltage
λ_{pm}	Permanent magnet flux linkage
P	Motor pole pairs

Transforms

To calculate the voltages and currents in balanced three-phase (a, b) quantities, quadrature two-phase (α, β) quantities, and rotating (d, q) reference frames, the block uses the Clarke and Park Transforms.

In the transform equations.

$$\omega_e = P\omega_m$$

$$\frac{d\theta_e}{dt} = \omega_e$$

Transform	Description	Equations
Clarke	Converts balanced three-phase quantities (a, b) into balanced two-phase quadrature quantities (α, β).	$x_\alpha = \frac{2}{3}x_a - \frac{1}{3}x_b - \frac{1}{3}x_c$ $x_\beta = \frac{\sqrt{3}}{2}x_b - \frac{\sqrt{3}}{2}x_c$
Park	Converts balanced two-phase orthogonal stationary quantities (α, β) into an orthogonal rotating reference frame (d, q).	$x_d = x_\alpha \cos\theta_e + x_\beta \sin\theta_e$ $x_q = -x_\alpha \sin\theta_e + x_\beta \cos\theta_e$
Inverse Clarke	Converts balanced two-phase quadrature quantities (α, β) into balanced three-phase quantities (a, b).	$x_a = x_\alpha$ $x_b = -\frac{1}{2}x_\alpha + \frac{\sqrt{3}}{2}x_\beta$ $x_c = -\frac{1}{2}x_\alpha - \frac{\sqrt{3}}{2}x_\beta$
Inverse Park	Converts an orthogonal rotating reference frame (d, q) into balanced two-phase orthogonal stationary quantities (α, β).	$x_\alpha = x_d \cos\theta_e - x_q \sin\theta_e$ $x_\beta = x_d \sin\theta_e + x_q \cos\theta_e$

The transforms use these variables.

ω_m	Rotor speed
P	Motor pole pairs

ω_e	Rotor electrical speed
Θ_e	Rotor electrical angle
x	Phase current or voltage

Motor

The block uses the phase currents and phase voltages to estimate the DC bus current. Positive current indicates battery discharge. Negative current indicates battery charge. The block uses these equations.

Load power	$Ld_{Pwr} = v_a i_a + v_b i_b + v_c i_c$
Source power	$Src_{Pwr} = Ld_{Pwr} + Pwr_{Loss}$
DC bus current	$i_{bus} = \frac{Src_{Pwr}}{v_{bus}}$
Estimated rotor torque	$MtrTrq_{est} = 1.5P[\lambda i_q + (L_d - L_q)i_d i_q]$
Power loss for single efficiency source to load	$Pwr_{Loss} = \frac{100 - Eff}{Eff} \cdot Ld_{Pwr}$
Power loss for single efficiency load to source	$Pwr_{Loss} = \frac{100 - Eff}{100} \cdot Ld_{Pwr} $
Power loss for tabulated efficiency	$Pwr_{Loss} = f(\omega_m, MtrTrq_{est})$

The equations use these variables.

v_a, v_b, v_c	Stator phase a, b, c voltages
v_{bus}	Estimated DC bus voltage
i_a, i_b, i_c	Stator phase a, b, c currents
i_{bus}	Estimated DC bus current
Eff	Overall inverter efficiency
ω_m	Rotor mechanical speed
L_q	q-axis winding inductance
L_d	d-axis winding inductance
i_q	q-axis current
i_d	d-axis current
λ	Permanent magnet flux linkage
P	Motor pole pairs

Electrical Losses

To specify the electrical losses, on the **Electrical Losses** tab, for **Parameterize losses by**, select one of these options.

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.

Setting	Block Implementation
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use **Tabulated loss data** instead of **Tabulated efficiency data**:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Ports

Input

SpdReq — Rotor speed command

scalar

Rotor speed command, ω_m^* , in rad/s.

Dependencies

To create this port, select **Speed Control** for the **Control Type** parameter.

TrqCmd — Torque command

scalar

Torque command, T^* , in N·m.

Dependencies

To create this port, select **Torque Control** for the **Control Type** parameter.

BusVolt — DC bus voltage

scalar

DC bus voltage, v_{bus} , in V.

PhaseCurrA — Current

scalar

Stator current phase a, i_a , in A.

PhaseCurrB – Current

scalar

Stator current phase b, i_b , in A.

SpdFdbk – Rotor speed

scalar

Rotor speed, ω_m , in rad/s.

PosFdbk – Rotor electrical angle

scalar

Rotor electrical angle, θ_m , in rad.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
SrcPwr	Source power	W
LdPwr	Load power	W
PwrLoss	Power loss	W
MtrTrqEst	Estimated motor torque	N·m

BusCurr – Bus current

scalar

Estimated DC bus current, i_{bus} , in A.

PhaseVolt – Stator terminal voltages

array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Parameters

Block Options

Control Type – Select control

Speed Control (default) | Torque Control

If you select Torque Control, the block does not implement the speed controller.

This table summarizes the port configurations.

Port Configuration	Creates Ports
Speed Control	SpdReq

Port Configuration	Creates Ports
Torque Control	TrqCmd

Motor Parameters

Stator resistance, R_s — Resistance

0.02 (default) | scalar

Stator phase winding resistance, R_s , in ohm.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Stator resistance, R_s	D and Q axis integral gain, K_i	Current Controller

D-axis inductance, L_d — Inductance

1.7e-3 (default) | scalar

D-axis winding inductance, L_d , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
D-axis inductance, L_d	Torque Breakpoints, T_{mtpa} D-axis table data, id_{mtpa} Q-axis table data, iq_{mtpa} D, q, and max current limits, idq_limits	Id and Iq Calculation

Q-axis inductance, L_q — Inductance

3.2e-3 (default) | scalar

Q-axis winding inductance, L_q , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Q-axis inductance, Lq	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

Permanent magnet flux, lambda_pm – Flux

0.2205 (default) | scalar

Permanent magnet flux, λ_{pm} , in Wb.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Permanent magnet flux, lambda_pm	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

Number of pole pairs, PolePairs – Poles

4 (default) | scalar

Motor pole pairs, P .

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Number of pole pairs, PolePairs	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

Physical inertia, viscous damping, static friction, Mechanical – Inertia, damping, friction

[0.0027, 4.924e-4, 0] (default) | vector

Mechanical properties of the motor:

- Motor inertia, F_v , in kgm^2
- Viscous friction torque constant, F_v , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction torque constant, F_s , in $\text{N}\cdot\text{m}$

DependenciesTo enable this parameter, set the **Control Type** parameter to Speed Control.For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value that is on the **Motor Parameters** tab.

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Physical inertia, viscous damping, static friction, Mechanical	Proportional gain, ba Angular gain, Ksa Rotational gain, Kisa Inertia compensation, Jcomp Viscous damping compensation, Fv Static friction, Fs	Speed Controller

Id and Iq Calculation**Motor constraint – Motor constraint**

Maximum Torque (default) | Maximum Current

Motor constraint for MTPA control.

Maximum current, I_max – Current

44 (default) | scalar

Maximum current, in A.

DependenciesTo enable this parameter, set **Motor constraint** to Maximum Current.

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Maximum torque, T_max	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

Maximum torque, T_max – Torque

60 (default) | scalar

Maximum torque, in N·m.

Dependencies

To enable this parameter, set **Motor constraint** to Maximum Torque.

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Maximum torque, T_max	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

MTPA table breakpoints, bp – Number of breakpoints

10 (default) | scalar

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
MTPA table breakpoints, pb	Torque Breakpoints, T_mtpa D-axis table data, id_mtpa Q-axis table data, iq_mtpa D, Q, and max current limits, idq_limits	Id and Iq Calculation

Calculate MTPA Table Data – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Id and Iq Calculation** tab, when you select **Calculate MPTA Table data**, the block calculates derived parameters. The table summarizes the derived parameter dependencies on other block parameters.

Derived Parameter on Id and Iq Calculation tab		Depends On	
		Parameter	Tab
Torque Breakpoints, T_mtpa	$T_{mtpa} = \frac{3}{2}P(\lambda_{pm}i_q + (L_d - L_q)i_d i_q)$	Maximum torque, T_max MPTA table breakpoints, pb	Id and Iq Calculation
D-axis table data, id_mtpa	$I_m = \frac{2T_{max}}{3P\lambda_{pm}}$ $i_{d_mtpa} = \frac{\lambda_{pm}}{4(L_q - L_d)} - \sqrt{\frac{\lambda_{pm}^2}{16(L_q - L_d)^2} + \frac{T_{mtpa}}{2L_d}}$	Permanent magnet flux, lambda_pm D-axis inductance, Ld	Motor Parameters
Q-axis table data, iq_mtpa	$i_{q_mtpa} = \sqrt{I_m^2 - (i_{mtpa})^2}$	Q-axis inductance, Lq	
D, Q, and max current limits, idq_limits		Number of pole pairs, PolePairs	

The equations use these variables.

i_{max}	Maximum phase current
i_d	d-axis current
i_q	q-axis current
i_{d_max}	Maximum d-axis phase current
i_{q_max}	Maximum q-axis phase current
i_{d_mtpa}	d-axis phase current MPTA table
i_{q_mtpa}	q-axis phase current MPTA table
λ_{pm}	Permanent magnet flux linkage
L_d	d-axis winding inductance
L_q	q-axis winding inductance
P	Motor pole pairs
T_{mtpa}	Torque MPTA breakpoints
I_m	Estimated maximum current

Torque Breakpoints, T_mtpa – Derived

[0 6.41323967543524 12.8472271930531 19.3221671098192 25.8572437875407 32.4702594835269 39.177408529382 45.9931820911486 52.930379967864 60.0001984561834] (default) | vector

Derived torque breakpoints, in N·m.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Torque Breakpoints, T_mtpa	Maximum torque, T_max	Id and Iq Calculation
	MTPA table breakpoints, pb	
	Permanent magnet flux, lambda_pm	Motor Parameters
	D-axis inductance, Ld	
	Q-axis inductance, Lq	
Number of pole pairs, PolePairs		

D-axis table data, id_mtpa – Derived

[0 -0.159333276810563 -0.633258709677809 -1.41005695027301 -2.47173666500257 -3.79592548539108 -5.35786489234899 -7.13217478652462 -9.09420364751938 -11.2209236729158] (default) | vector

Derived d-axis table data, in A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D-axis table data, id_mtpa	Maximum torque, T_max	Id and Iq Calculation
	MTPA table breakpoints, pb	
	Permanent magnet flux, lambda_pm	Motor Parameters
	D-axis inductance, Ld	
	Q-axis inductance, Lq	
Number of pole pairs, PolePairs		

Q-axis table data, iq_mtpa – Derived

[0 4.84224935172196 9.66902512748937 14.4660510262181 19.2212063070062 23.9250934510846 28.5711892538614 33.1556572971289 37.6769488702032 42.1353166357157] (default) | vector

Derived q-axis table data, in A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D-axis table data, id_mtpa	Maximum torque, T_max	Id and Iq Calculation
	MTPA table breakpoints, pb	
	Permanent magnet flux, lambda_pm	Motor Parameters
	D-axis inductance, Ld	
	Q-axis inductance, Lq	
	Number of pole pairs, PolePairs	

D, Q, and max current limits, idq_limits – Derived

[-11.2210468862948 42.1352838229553 43.6038305205566] (default) | array

Derived d, q, and maximum current limits, in A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D, Q, and max current limits, idq_limits	Maximum torque, T_max	Id and Iq Calculation
	MTPA table breakpoints, pb	
	Permanent magnet flux, lambda_pm	Motor Parameters
	D-axis inductance, Ld	
	Q-axis inductance, Lq	
	Number of pole pairs, PolePairs	

Current Controller**Bandwidth of the current regulator, EV_current – Bandwidth**

200 (default) | scalar

Derived current regulator bandwidth, in Hz.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the current regulator, EV_current	D-axis proportional gain, Kp_d	Current Controller
	Q-axis proportional gain, Kp_q	
	D and Q axis proportional gain, Ki	

Sample time for the torque control, Tst – Time

5e-5 (default) | scalar

Derived torque control sample time, in s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Sample time for the torque control, Tst	Speed regulation time constant, Ksf	Speed Controller

Calculate Current Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Current Controller** tab, when you select **Calculate Current Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameter dependencies on other block parameters.

Derived Parameter on Current Controller tab	Dependency	
	Parameter	Tab
D-axis proportional gain, Kp_d	Bandwidth of the current regulator, EV_current	Current Controller
Q-axis proportional gain, Kp_q	Stator resistance, Rs	Motor Parameters
D and Q axis integral gain, Ki		

D-axis proportional gain, Kp_d – Derived

2.1363 (default) | scalar

Derived d-axis proportional gain, in V/A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D-axis proportional gain, Kp_d	Bandwidth of the current regulator, EV_current	Current Controller

Q-axis proportional gain, Kp_q – Derived

4.0212 (default) | scalar

Derived q-axis proportional gain, in V/A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Q-axis proportional gain, Kp_q	Bandwidth of the current regulator, EV_current	Current Controller

D and Q axis integral gain, Ki – Derived

25.1327 (default) | scalar

Derived d- and q- axis integral gains, in V/A·s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D and Q axis integral gain, Ki	Stator resistance, Rs	Motor Parameters

Speed Controller**Bandwidth of the motion controller, EV_motion – Bandwidth**

[20, 4, 0.8] (default) | vector

Motion controller bandwidth, in Hz. Set the first element of the vector to the desired cutoff frequency. Set the second and third elements of the vector to the higher-order cut off frequencies. You can set the value of the next element to 1/5 the value of the previous element. For example, if the desired cutoff frequency is 20 Hz, specify [20 4 0.8].

DependenciesThe parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the motion controller, EV_motion	Proportional gain, ba	Speed Controller
	Angular gain, Ksa	
	Rotational gain, Kisa	

Bandwidth of the state filter, EV_sf – Bandwidth

200 (default) | scalar

State filter bandwidth, in Hz.

Dependencies

The parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the state filter, EV_sf	Speed regulation time constant, Ksf	Speed Controller

Calculate Speed Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Speed Controller** tab, when you select **Calculate Speed Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Speed Controller tab		Depends On	
		Parameter	Tab
Proportional gain, ba	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$	Bandwidth of the motion controller, EV_motion Bandwidth of the state filter, EV_sf	Speed Controller
Angular gain, Ksa	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$	Sample time for the torque control, Tst	Current Controller
Rotational gain, Kisa	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Derived Parameter on Speed Controller tab		Depends On	
		Parameter	Tab
Speed regulation time constant, Ksf	$K_{sf} = \frac{1 - \exp(-T_{sm}2\pi EV_{sf})}{T_{sm}}$		
Inertia compensation, Jcomp	$J_{comp} = J_p$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
Viscous damping compensation, Fv	F_v		
Static friction, Fs	F_s		

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
K_{sf}	Speed regulator time constant
J_p	Motor inertia
EV_{sf}	State filter bandwidth
EV_{motion}	Motion controller bandwidth

Proportional gain, ba – Derived

3.7477 (default) | scalar

Derived proportional gain, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Proportional gain, ba	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_motion	Speed Controller

Angular gain, Ksa – Derived

94.0877 (default) | scalar

Derived angular gain, in N·m/rad.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Angular gain, Ksa	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_motion	Speed Controller

Rotational gain, Kisa – Derived

381.7822 (default) | scalar

Derived rotational gain, in N·m/(rad*s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Rotational gain, Kisa	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_motion	Speed Controller

Speed regulation time constant, Ksf – Derived

1217.9727 (default) | scalar

Derived speed regulation time constant, in 1/s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Speed regulation time constant, Ksf	Sample time for the torque control, Tst	Current Controller
	Bandwidth of the state filter, EV_sf	Speed Controller

Inertia compensation, Jcomp – Derived

0.025 (default) | scalar

Derived inertia compensation, in kg·m².

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Inertia compensation, Jcomp	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Viscous damping compensation, Fv – Derived

0 (default) | scalar

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Viscous damping compensation, Fv	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Static friction, Fs – Derived

0 (default) | scalar

Derived static friction, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Static friction, Fs	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Electrical Losses**Parameterize losses by – Select type**

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.

Setting	Block Implementation
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use `Tabulated loss data` instead of `Tabulated efficiency data`:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Overall inverter efficiency, *eff* – Constant

98 (default) | scalar

Overall inverter efficiency, *Eff*, in %.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Vector of speeds (w) for tabulated loss, *w_loss_bp* – Breakpoints

[0 200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating losses, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Vector of torques (T) for tabulated loss, *T_loss_bp* – Breakpoints

[0 25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating losses, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Corresponding losses, *losses_table* – Table

[100 100 100 100 100;100 150 200 250 300;100 200 300 400 500;100 250 400 550 700;100 300 500 700 900;100 350 600 850 1100] (default) | M-by-N array

Array of values for electrical losses as a function of M speeds and N torques, in W. Each value specifies the losses for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of speeds (w) for tabulated efficiency, w_eff_bp – Breakpoints

[200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating efficiency, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Vector of torques (T) for tabulated efficiency, T_eff_bp – Breakpoints

[25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating efficiency, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Corresponding efficiency, efficiency_table – Table

[96.2 98.1 98.7 99;98.1 99 99.4 99.5;98.7 99.4 99.6 99.7;99 99.5 99.7 99.8;99.2 99.6 99.7 99.8] (default) | M-by-N array

Array of efficiency as a function of M speeds and N torque, in %. Each value specifies the efficiency for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Version History

Introduced in R2017a

References

- [1] Lorenz, Robert D., Thomas Lipo, and Donald W. Novotny. "Motion control with induction motors." *Proceedings of the IEEE*, Vol. 82, Issue 8, August 1994, pp. 1215-1240.
- [2] Morimoto, Shigeo, Masayuka Sanada, and Yoji Takeda. "Wide-speed operation of interior permanent magnet synchronous motors with high-performance current regulator." *IEEE Transactions on Industry Applications*, Vol. 30, Issue 4, July/August 1994, pp. 920-926.
- [3] Li, Muyang. "Flux-Weakening Control for Permanent-Magnet Synchronous Motors Based on Z-Source Inverters." Master's Thesis, Marquette University, e-Publications@Marquette, Fall 2014.

- [4] Briz, Fernando, Michael W. Degner, and Robert D. Lorenz. "Analysis and design of current regulators using complex vectors." *IEEE Transactions on Industry Applications*, Vol. 36, Issue 3, May/June 2000, pp. 817-825.
- [5] Briz, Fernando, et al. "Current and flux regulation in field-weakening operation [of induction motors]." *IEEE Transactions on Industry Applications*, Vol. 37, Issue 1, Jan/Feb 2001, pp. 42-50.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

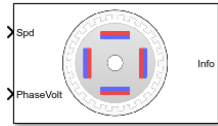
See Also

Interior PMSM | Flux-Based PM Controller | IM Controller | Surface Mount PM Controller

Flux-Based PMSM

Flux-based permanent magnet synchronous motor

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters



Description

The Flux-Based PMSM block implements a flux-based three-phase permanent magnet synchronous motor (PMSM) with a tabular-based electromotive force. The block uses the three-phase input voltages to regulate the individual phase currents, allowing control of the motor torque or speed.

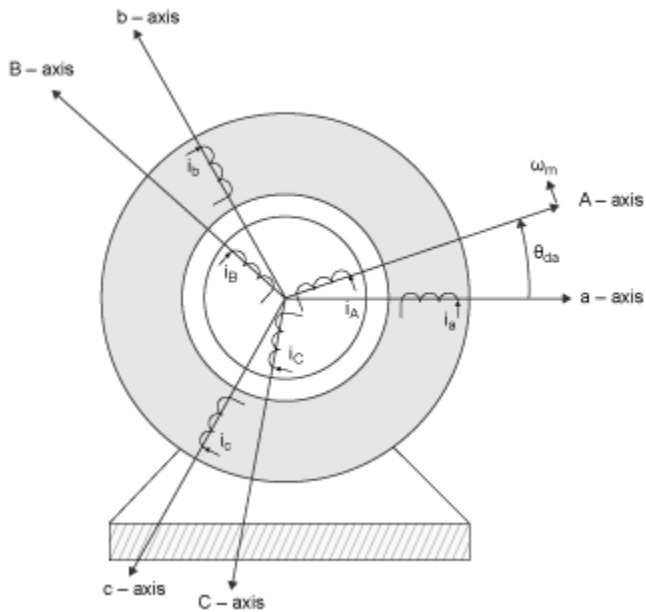
Flux-based motor models take into account magnetic saturation and iron losses. To calculate the magnetic saturation and iron loss, the Flux-Based PMSM block uses the inverse of the flux linkages. To obtain the block parameters, you can use finite-element analysis (FEA) or measure phase voltages using a dynamometer.

By default, the block sets the **Simulation Type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

To enable power loss calculations suitable for code generation targets that limit memory, select **Enable memory optimized 2D LUT**.

Three-Phase Sinusoidal Model Electrical System

The block implements equations that are expressed in a stationary rotor reference (dq) frame. The d -axis aligns with the a -axis. All quantities in the rotor reference frame are referred to the stator.



The block uses these equations.

Calculation	Equation
q - and d -axis voltage	$v_d = \frac{d\psi_d}{dt} + R_s i_d - \omega_e \psi_q$ $v_q = \frac{d\psi_q}{dt} + R_s i_q + \omega_e \psi_d$
q - and d -axis current	$i_d = f(\psi_d, \psi_q)$ $i_q = g(\psi_d, \psi_q)$
Electromechanical torque	$T_e = 1.5P[\psi_d i_q - \psi_q i_d]$

The equations use these variables.

- ω_m Rotor mechanical speed
- ω_e Rotor electrical speed
- θ_{da} dq stator electrical angle with respect to the rotor a-axis
- R_s, R_r Resistance of the stator and rotor windings, respectively
- i_q, i_d q - and d -axis current, respectively
- v_q, v_d q - and d -axis voltage, respectively
- ψ_q, ψ_d q - and d -axis magnet flux, respectively
- P Number of pole pairs
- T_e Electromagnetic torque

Transforms

To calculate the voltages and currents in balanced three-phase (a, b) quantities, quadrature two-phase (α, β) quantities, and rotating (d, q) reference frames, the block uses the Clarke and Park Transforms.

In the transform equations.

$$\omega_e = P\omega_m$$

$$\frac{d\theta_e}{dt} = \omega_e$$

Transform	Description	Equations
Clarke	Converts balanced three-phase quantities (a, b) into balanced two-phase quadrature quantities (α, β).	$x_\alpha = \frac{2}{3}x_a - \frac{1}{3}x_b - \frac{1}{3}x_c$ $x_\beta = \frac{\sqrt{3}}{2}x_b - \frac{\sqrt{3}}{2}x_c$
Park	Converts balanced two-phase orthogonal stationary quantities (α, β) into an orthogonal rotating reference frame (d, q).	$x_d = x_\alpha \cos\theta_e + x_\beta \sin\theta_e$ $x_q = -x_\alpha \sin\theta_e + x_\beta \cos\theta_e$
Inverse Clarke	Converts balanced two-phase quadrature quantities (α, β) into balanced three-phase quantities (a, b).	$x_a = x_\alpha$ $x_b = -\frac{1}{2}x_\alpha + \frac{\sqrt{3}}{2}x_\beta$ $x_c = -\frac{1}{2}x_\alpha - \frac{\sqrt{3}}{2}x_\beta$
Inverse Park	Converts an orthogonal rotating reference frame (d, q) into balanced two-phase orthogonal stationary quantities (α, β).	$x_\alpha = x_d \cos\theta_e - x_q \sin\theta_e$ $x_\beta = x_d \sin\theta_e + x_q \cos\theta_e$

The transforms use these variables.

ω_m	Rotor mechanical speed
P	Motor pole pairs
ω_e	Rotor electrical speed
θ_e	Rotor electrical angle
x	Phase current or voltage

Mechanical System

The rotor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of rotor and load
F	Combined viscous friction of rotor and load
θ_m	Rotor mechanical angular position
T_m	Rotor shaft torque
T_e	Electromagnetic torque
T_f	Combined rotor and load friction torque
ω_m	Rotor mechanical speed

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	P_{mot}	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	P_{bus}	$P_{bus} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	P_{elec}	$P_{elec} = -\frac{3}{2}(R_s i_{sd}^2 + R_s i_{sq}^2)$
	<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMechLoss	Mechanical power loss	P_{mech}	<p>When Port Configuration is set to Torque:</p> $P_{mech} = -(\omega_m^2 F + \omega_m T_f)$ <p>When Port Configuration is set to Speed:</p> $P_{mech} = 0$
PwrStored — Stored energy rate of change	PwrMtrStored	Stored motor power	P_{str}	$P_{str} = P_{bus} + P_{mot} + P_{elec} + P_{mech}$	
<ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 					

The equations use these variables.

R_s	Stator resistance
-------	-------------------

i_a, i_b, i_c	Stator phase a, b, and c current
i_{sq}, i_{sd}	Stator q- and d-axis currents
v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage
ω_m	Angular mechanical velocity of the rotor
F	Combined motor and load viscous damping
T_e	Electromagnetic torque
T_f	Combined motor and load friction torque

Lookup Table Memory Optimization

The data for the **Corresponding d-axis current, i_d** and **Corresponding q-axis current, i_q** lookup tables are functions of the d - and q -axis flux.

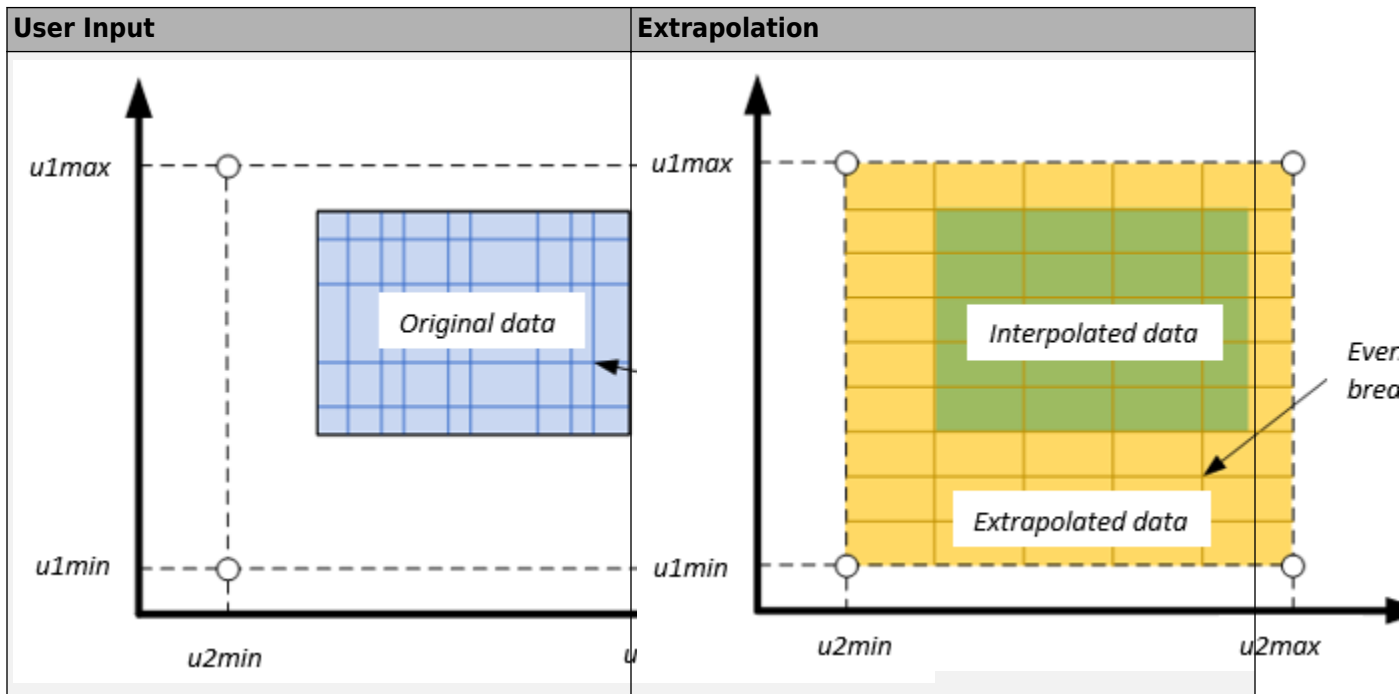
To enable current calculations suitable for code generation targets that limit memory, select **Enable memory optimized 2D LUT**. The block uses linear interpolation to optimize the current lookup table values for code generation. This table summarizes the optimization implementation.

Use Case	Implementation
d - and q -axis flux aligns with the lookup table breakpoint values.	Memory-optimized current is current lookup table value at intersection of flux values.
d - and q -axis flux does not align with the lookup table breakpoint values, but is within range.	Memory-optimized current is linear interpolation between corresponding flux values.
d - and q -axis flux does not align with the lookup table breakpoint values, and is out of range.	Cannot compute an memory-optimized current. Block uses extrapolated data.

Extrapolation

The lookup tables optimized for code generation do not support extrapolation for data that is out of range. However, you can include pre-calculated extrapolation values in the power loss lookup table by selecting **Specify Extrapolation**.

The block uses the endpoint parameters to resize the table data.



Ports

Input

LdTrq – Rotor shaft torque

scalar

Rotor shaft input torque, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port Configuration** parameter.

Spd – Rotor shaft speed

scalar

Angular velocity of the rotor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port Configuration** parameter.

PhaseVOLT – Stator terminal voltages

1-by-3 array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Dependencies

To create this port, select Speed or Torque for the **Port Configuration** parameter.

Output

Info — Bus signal

bus

The bus signal contains these block calculations.

Signal	Description	Variable	Units		
IaStator	Stator phase current A	i_a	A		
IbStator	Stator phase current B	i_b	A		
IcStator	Stator phase current C	i_c	A		
IdSync	Direct axis current	i_d	A		
IqSync	Quadrature axis current	i_q	A		
VdSync	Direct axis voltage	v_d	V		
VqSync	Quadrature axis voltage	v_q	V		
MtrSpd	Angular mechanical velocity of the rotor	ω_m	rad/s		
MtrPos	Rotor mechanical angular position	θ_m	rad		
MtrTrq	Electromagnetic torque	T_e	N·m		
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr — Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq — Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Port configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Port configuration** parameter.

Parameters

Block Options

Simulation type — Select simulation type

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to Discrete.

Dependencies

Setting **Simulation Type** to Discrete creates the **Sample Time, Ts** parameter.

Sample time, Ts — Sample time for discrete integration

0.001 (default) | scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation Type** to Discrete creates the **Sample Time, Ts** parameter.

Port Configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd
Speed	Spd	MtrTrq

Enable memory optimized 2D LUT — Selection

off (default) | on

Enable generation of optimized lookup tables, suitable code generation targets that limit memory.

Vector of d-axis flux, flux_d — Flux breakpoints

1-by-M vector

d -axis flux, Ψ_d , breakpoints, in Wb.

Resample storage size for flux_d, n1 — Flux bit size

2 (default) | 4 | 8 | 16 | 32 | 64 | 128 | 256

Flux breakpoint storage size, $n1$, dimensionless. The block resamples the **Corresponding d-axis current, id** and **Corresponding q-axis current, iq** data based on the storage size.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT**.

Vector of q-axis flux, flux_q — Flux breakpoints

1-by-N vector

q -axis flux, Ψ_q , breakpoints, in Wb.

Resample storage size for flux_q, n2 — Flux bit size

2 (default) | 4 | 8 | 16 | 32 | 64 | 128 | 256

Flux breakpoint storage size, $n2$, dimensionless. The block resamples the **Corresponding d-axis current, id** and **Corresponding q-axis current, iq** data based on the storage size.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT**.

Corresponding d-axis current, id — 2D lookup table

M-by-N array

Array of values for d -axis current, i_d , as a function of M d -fluxes, Ψ_d , and N q -fluxes, Ψ_q , in A. Each value specifies the current for a specific combination of d - and q -axis flux. The array size must match the dimensions defined by the flux vectors.

If you set **Enable memory optimized 2D LUT**, the block converts the data to single precision.

Corresponding q-axis current, iq — 2D lookup table

M-by-N array

Array of values for q -axis current, i_q , as a function of M d -fluxes, Ψ_d , and N q -fluxes, Ψ_q , in A. Each value specifies the current for a specific combination of d - and q -axis flux. The array size must match the dimensions defined by the flux vectors.

If you set **Enable memory optimized 2D LUT**, the block converts the data to single precision.

flux_d max endpoint, u1max — Flux breakpoint

0.22457 (default) | scalar

Flux breakpoint maximum extrapolation endpoint, $u1max$, in Wb.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

flux_d min endpoint, u1min — Flux breakpoint

-0.22607 (default) | scalar

Flux breakpoint minimum extrapolation endpoint, $u1min$, in Wb.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

flux_q max endpoint, u2max — Flux breakpoint

0.42959 (default) | scalar

Flux breakpoint maximum extrapolation endpoint, $u2max$, in Wb.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

flux_q min endpoint, u2min — Flux breakpoint

-0.4296 (default) | scalar

Flux breakpoint minimum extrapolation endpoint, $u2min$, in Wb.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

Stator phase resistance, R_s — Resistance

0.02 (default) | scalar

Stator phase resistance, R_s , in ohm.

Number of pole pairs, P — Pole pairs

4 (default) | scalar

Motor pole pairs, P .

Initial flux, fluxdq0 — Flux

[0 0] (default) | vector

Initial d - and q -axis flux, Ψ_{q0} and Ψ_{d0} , in Wb.

Initial mechanical position, theta_init — Angle

0 (default) | scalar

Initial rotor angular position, θ_{m0} , in rad.

Initial mechanical speed, omega_init — Speed

0 (default) | scalar

Initial angular velocity of the rotor, ω_{m0} , in rad/s.

Dependencies

To enable this parameter, select the Torque configuration parameter.

Physical inertia, viscous damping, and static friction, mechanical — Inertia, damping, friction

[0.0027, 4.924e-4, 0] (default) | vector

Mechanical properties of the rotor:

- Inertia, J , in kgm^2
- Viscous damping, F , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction, T_f , in $\text{N}\cdot\text{m}$

Dependencies

To enable this parameter, select the Torque configuration parameter.

Version History

Introduced in R2017b

References

- [1] Hu, Dakai, Yazan Alsmadi, and Longya Xu. "High fidelity nonlinear IPM modeling based on measured stator winding flux linkage." *IEEE Transactions on Industry Applications*, Vol. 51, No. 4, July/August 2015.
- [2] Chen, Xiao, Jiabin Wang, Bhaskar Sen, Panagiotis Lasari, Tianfu Sun. "A High-Fidelity and Computationally Efficient Model for Interior Permanent-Magnet Machines Considering the Magnetic Saturation, Spatial Harmonics, and Iron Loss Effect." *IEEE Transactions on Industrial Electronics*, Vol. 62, No. 7, July 2015.
- [3] Ottosson, J., M. Alakula. "A compact field weakening controller implementation." *International Symposium on Power Electronics, Electrical Drives, Automation and Motion*, July, 2006.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Flux-Based PM Controller | Induction Motor | Interior PMSM | Mapped Motor | Surface Mount PMSM

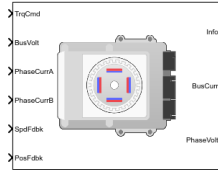
Topics

"Generate Optimal Current Controller Calibration Tables for Permanent Magnet Synchronous Motors"

Flux-Based PM Controller

Controller for a flux-based permanent magnet synchronous motor

Library: Powertrain Blockset / Propulsion / Electric Motor Controllers

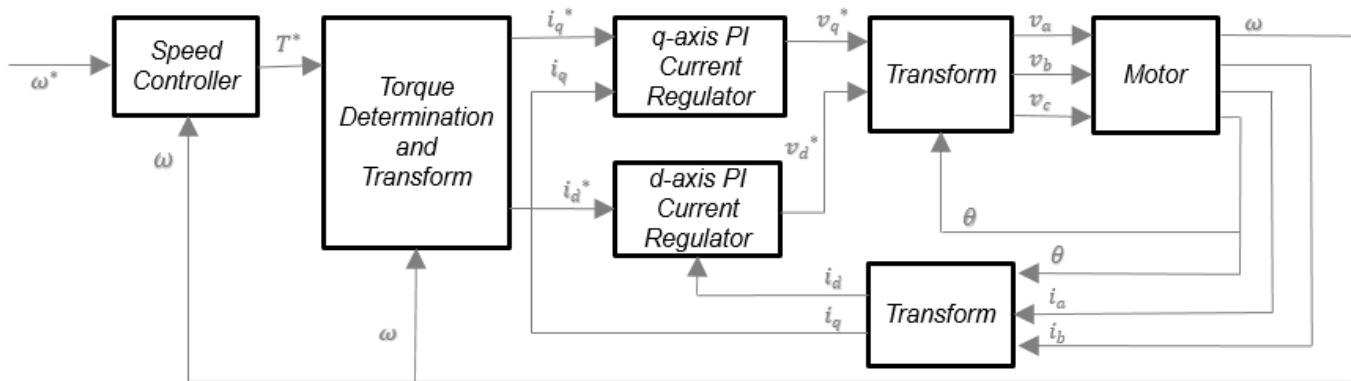


Description

The Flux Based PM Controller block implements a flux-based, field-oriented controller for an interior permanent magnet synchronous motor (PMSM) with an optional outer-loop speed controller. The internal torque control implements strategies for achieving maximum torque per ampere (MTPA) and weakening the magnetic flux. You can specify either the speed or torque control type.

The Flux Based PM Controller implements equations for speed control, torque determination, regulators, transforms, and motors.

The figure illustrates the information flow in the block.



The block implements equations using these variables.

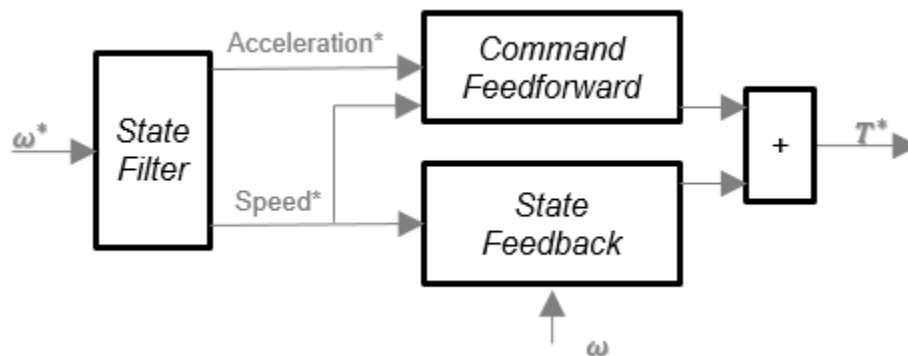
ω	Rotor speed
ω^*	Rotor speed command
T^*	Torque command
i_d	d -axis current
i_d^*	d -axis current command
i_q	q -axis current
i_q^*	q -axis current command

v_d	d -axis voltage
v_d^*	d -axis voltage command
v_q	q -axis voltage
v_q^*	q -axis voltage command
v_a, v_b, v_c	Stator phase a, b, c voltages
i_a, i_b, i_c	Stator phase a, b, c currents

Speed Controller

To implement the speed controller, select the **Control Type** parameter `Speed Control`. If you select the **Control Type** parameter `Torque Control`, the block does not implement the speed controller.

The speed controller determines the torque command by implementing a state filter, and calculating the feedforward and feedback commands. If you do not implement the speed controller, input a torque command to the Flux Based PM Controller block.



State Filter

The state filter is a low-pass filter that generates the acceleration command based on the speed command. The discrete form of characteristic equation is given by:

$$z + K_{sf}T_{sm} - 1$$

The filter calculates the gain using this equation.

$$K_{sf} = \frac{1 - \exp(-T_{sm}2\pi EV_{sf})}{T_{sm}}$$

The equations use these variables.

EV_{sf}	Bandwidth of the speed command filter
T_{sm}	Motion controller sample time
K_{sf}	Speed regulator time constant

State Feedback

To generate the state feedback torque, the block uses the filtered speed error signal from the state filter. To filter the speed, the block uses a proportional integral (PI) controller.

$$T_{cmd} = Kp_{\omega}(\omega_m^* - \omega_m) + Ki_{\omega} \frac{zT_{sm}}{z-1}(\omega_m^* - \omega_m)$$

The equations use these variables.

ω_m	Rotor speed
ω_m^*	Rotor speed command
T_{cmd}	Torque command
Kp_{ω}	Speed regulator proportional gain
Ki_{ω}	Speed regulator integral gain
T_{sm}	Speed regulator sample rate

Command Feedforward

To generate the state feedforward torque, the block uses the filtered speed and acceleration from the state filter. Also, the feedforward torque calculation uses the inertia, viscous damping, and static friction. To achieve zero tracking error, the torque command is the sum of the feedforward and feedback torque commands.

The feedforward torque command uses this equation.

$$T_{cmd_ff} = J_p \dot{\omega}_m + F_v \omega_m + F_s \frac{\omega_m}{|\omega_m|}$$

where:

J_p	Rotor inertia
T_{cmd_ff}	Torque command feedforward
F_s	Static friction torque constant
F_v	Viscous friction torque constant
F_s	Static friction torque constant
ω_m	Rotor speed

Current Command

The block uses lookup tables to determine the d -axis and q -axis current commands. The lookup tables are functions of mechanical speed and torque. To determine the lookup tables, you can use an external finite element analysis (FEA) models or dynamometer test results.

$$i_{dref} = f(|\omega_m|, |T_{ref}|)$$

$$i_{qref} = \text{sign}(T_{ref}) * f(|\omega_m|, |T_{ref}|)$$

The equations use these variables.

ω_m	Rotor speed
T_{ref}	Torque command
i_{dref}, i_{qref}	d - and q -axis reference current, respectively

Voltage Command

The block uses these equations to calculate the voltage in the motor reference frame.

$$v_d = \frac{d\psi_d}{dt} + R_s i_d - \omega_e \psi_q$$

$$v_q = \frac{d\psi_q}{dt} + R_s i_q + \omega_e \psi_d$$

$$\frac{d\psi_d}{dt} + R_s i_d = K p_d (i_d^* - i_d) + K i_d \frac{z T_{st}}{z - 1} (i_d^* - i_d)$$

$$\frac{d\psi_q}{dt} + R_s i_q = K p_q (i_q^* - i_q) + K i_q \frac{z T_{st}}{z - 1} (i_q^* - i_q)$$

$$v_d = K p_i (i_d^* - i_d) + K i_d \frac{z T_{st}}{z - 1} (i_d^* - i_d) + \omega_e \psi_q$$

$$v_q = K p_i (i_q^* - i_q) + K i_q \frac{z T_{st}}{z - 1} (i_q^* - i_q) - \omega_e \psi_d$$

$$\psi_q = f(i_d, i_q)$$

$$\psi_d = f(i_d, i_q)$$

The equations use these variables.

ω_m	Rotor mechanical speed
ω_e	Rotor electrical speed
R_s, R_r	Resistance of the stator and rotor windings, respectively
i_q, i_d	q - and d -axis current, respectively
v_q, v_d	q - and d -axis voltage, respectively
Ψ_q, Ψ_d	q - and d -axis magnet flux, respectively
T_{st}	Current regulator sample rate
$K i_d, K i_q$	d - and q - axis integral gain, respectively
$K p_d, K p_q$	d - and q - axis proportional gain, respectively

Transforms

To calculate the voltages and currents in balanced three-phase (a, b) quantities, quadrature two-phase (α, β) quantities, and rotating (d, q) reference frames, the block uses the Clarke and Park Transforms.

In the transform equations.

$$\omega_e = P \omega_m$$

$$\frac{d\theta_e}{dt} = \omega_e$$

Transform	Description	Equations
Clarke	Converts balanced three-phase quantities (a, b) into balanced two-phase quadrature quantities (α, β).	$x_\alpha = \frac{2}{3}x_a - \frac{1}{3}x_b - \frac{1}{3}x_c$ $x_\beta = \frac{\sqrt{3}}{2}x_b - \frac{\sqrt{3}}{2}x_c$
Park	Converts balanced two-phase orthogonal stationary quantities (α, β) into an orthogonal rotating reference frame (d, q).	$x_d = x_\alpha \cos\theta_e + x_\beta \sin\theta_e$ $x_q = -x_\alpha \sin\theta_e + x_\beta \cos\theta_e$
Inverse Clarke	Converts balanced two-phase quadrature quantities (α, β) into balanced three-phase quantities (a, b).	$x_a = x_\alpha$ $x_b = -\frac{1}{2}x_\alpha + \frac{\sqrt{3}}{2}x_\beta$ $x_c = -\frac{1}{2}x_\alpha - \frac{\sqrt{3}}{2}x_\beta$
Inverse Park	Converts an orthogonal rotating reference frame (d, q) into balanced two-phase orthogonal stationary quantities (α, β).	$x_\alpha = x_d \cos\theta_e - x_q \sin\theta_e$ $x_\beta = x_d \sin\theta_e + x_q \cos\theta_e$

The transforms use these variables.

ω_m	Rotor speed
P	Rotor pole pairs
ω_e	Rotor electrical speed
θ_e	Rotor electrical angle
x	Phase current or voltage

Motor

The block uses the phase currents and phase voltages to estimate the DC bus current. Positive current indicates battery discharge. Negative current indicates battery charge.

The block uses these equations.

Load power	$Ld_{Pwr} = v_a i_a + v_b i_b + v_c i_c$
Source power	$Src_{Pwr} = Ld_{Pwr} + Pwr_{Loss}$
DC bus current	$i_{bus} = \frac{Src_{Pwr}}{v_{bus}}$
Estimated rotor torque	$T_e = 1.5P[\psi_d i_q - \psi_q i_d]$
Power loss for single efficiency source to load	$Pwr_{Loss} = \frac{100 - Eff}{Eff} \cdot Ld_{Pwr}$
Power loss for single efficiency load to source	$Pwr_{Loss} = \frac{100 - Eff}{100} \cdot Ld_{Pwr} $
Power loss for tabulated efficiency	$Pwr_{Loss} = f(\omega_m, MtrTrq_{est})$

The equations use these variables.

v_a, v_b, v_c	Stator phase a, b, c voltages
v_{bus}	Estimated DC bus voltage
i_a, i_b, i_c	Stator phase a, b, c currents
i_{bus}	Estimated DC bus current
Eff	Overall inverter efficiency
ω_m	Rotor mechanical speed
L_q, L_d	q - and d -axis winding inductance, respectively
Ψ_q, Ψ_d	q - and d -axis magnet flux, respectively
i_q, i_d	q - and d -axis current, respectively
λ	Permanent magnet flux linkage
P	Rotor pole pairs

Electrical Losses

To specify the electrical losses, on the **Electrical Losses** tab, for **Parameterize losses by**, select one of these options.

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use **Tabulated loss data** instead of **Tabulated efficiency data**:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Ports

Input

SpdReq — Rotor speed command
scalar

Rotor speed command, ω_m^* , in rad/s.

Dependencies

To create this port, select Speed Control for the **Control Type** parameter.

TrqCmd — Torque command

scalar

Torque command, T^* , in N·m.

Dependencies

To create this port, select Torque Control for the **Control Type** parameter.

BusVolt — DC bus voltage

scalar

DC bus voltage, v_{bus} , in V.

PhaseCurrA — Current

scalar

Stator current phase a, i_a , in A.

PhaseCurrB — Current

scalar

Stator current phase b, i_b , in A.

SpdFdbk — Rotor speed

scalar

Rotor speed, ω_m , in rad/s.

PosFdbk — Rotor electrical angle

scalar

Rotor electrical angle, θ_m , in rad.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
SrcPwr	Source power	W
LdPwr	Load power	W
PwrLoss	Power loss	W
MtrTrqEst	Estimated motor torque	N·m

BusCurr — Bus current

scalar

Estimated DC bus current, i_{bus} , in A.

PhaseVolt – Stator terminal voltages

array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Parameters

Block Options

Control Type – Select control

Torque Control (default) | Speed Control

If you select Torque Control, the block does not implement the speed controller.

This table summarizes the port configurations.

Port Configuration	Creates Ports
Speed Control	SpdReq
Torque Control	TrqCmd

Motor Parameters

Number of pole pairs, PolePairs – Poles

4 (default) | scalar

Motor pole pairs, P .

Vector of d-axis current breakpoints, id_index – Current

vector

d -axis current, i_{d_index} , in A.

Vector of q-axis current breakpoints, iq_index – current

vector

q -axis current, i_{q_index} , in A.

Corresponding d-axis flux, lambda_d – Flux

vector

d -axis flux, λ_d , in Wb.

Corresponding q-axis flux, lambda_q – Flux

vector

q -axis flux, λ_q , in Wb.

Current Controller

Sample time for the torque control, Tst – Time

1e-4 (default) | scalar

Torque control sample time, T_{st} , in s.

D-axis proportional gain, Kp_d – Gain

2.4056 (default) | scalar

d -axis proportional gain, Kp_d , in V/A.

Q-axis proportional gain, Kp_q – Gain

2.4056 (default) | scalar

q -axis proportional gain, Kp_q , in V/A.

D-axis integral gain, Ki_d – Gain

192.45 (default) | scalar

d -axis integral gain, Ki_d , in V/A·s.

Q-axis integral gain, Ki_q – Gain

192.45 (default) | scalar

q -axis integral gain, Ki_q , in V/A·s.

Vector of speed breakpoints, wpb – Breakpoints

vector

Speed breakpoints, ω_{bp} , in rad/s.

Vector of torque breakpoints, tpb – Breakpoints

vector

Torque breakpoints, T_{bp} , in N·m.

Corresponding d-axis current reference, id_ref – Current

vector

d -axis reference current, i_{dref} , in A.

Corresponding q-axis current reference, iq_ref – Current

vector

q -axis reference current, i_{qref} , in A.

Speed Controller

Speed regulation time constant, Ksf – Time

.1 (default) | scalar

Speed regulator time constant, K_{sf} , in 1/s.

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Proportional gain, Kp_w – Gain

0.40475 (default) | scalar

Proportional gain, Kp_w , in N·m/(rad/s).

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Integral gain, Ki_w – Gain

10.1615 (default) | scalar

Integral gain, Ki_w N·m/rad.

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Inertia compensation, $Jcomp$ – Inertia

0.0027 (default) | scalar

Inertia compensation, in $kg \cdot m^2$.

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Static friction, Fs – Friction

0 (default) | scalar

Static friction, in N·m.

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Viscous damping compensation, Fv – Dampint

0.0004924 (default) | scalar

Viscous damping compensation, in N·m/(rad/s).

Dependencies

To enable this parameter, for the **Control Type** parameter, select Speed Control.

Electrical Losses**Parameterize losses by – Select type**

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.

Setting	Block Implementation
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use `Tabulated loss data` instead of `Tabulated efficiency data`:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Overall inverter efficiency, *eff* – Constant

98 (default) | scalar

Overall inverter efficiency, *Eff*, in %.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Vector of speeds (w) for tabulated loss, *w_loss_bp* – Breakpoints

[0 200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating losses, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Vector of torques (T) for tabulated loss, *T_loss_bp* – Breakpoints

[0 25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating losses, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select `Tabulated loss data`.

Corresponding losses, *losses_table* – Table

[100 100 100 100 100;100 150 200 250 300;100 200 300 400 500;100 250 400 550 700;100 300 500 700 900;100 350 600 850 1100] (default) | M-by-N array

Array of values for electrical losses as a function of M speeds and N torques, in W. Each value specifies the losses for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of speeds (w) for tabulated efficiency, w_eff_bp – Breakpoints

[200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating efficiency, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Vector of torques (T) for tabulated efficiency, T_eff_bp – Breakpoints

[25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating efficiency, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Corresponding efficiency, efficiency_table – Table

[96.2 98.1 98.7 99;98.1 99 99.4 99.5;98.7 99.4 99.6 99.7;99 99.5 99.7 99.8;99.2 99.6 99.7 99.8] (default) | M-by-N array

Array of efficiency as a function of M speeds and N torque, in %. Each value specifies the efficiency for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Version History

Introduced in R2017b

References

- [1] Hu, Dakai, Yazan Alsmadi, and Longya Xu. "High fidelity nonlinear IPM modeling based on measured stator winding flux linkage." *IEEE Transactions on Industry Applications*, Vol. 51, No. 4, July/August 2015.
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See Also

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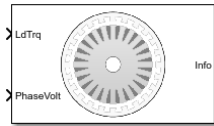
Topics

"Generate Optimal Current Controller Calibration Tables for Permanent Magnet Synchronous Motors"

Induction Motor

Three-phase induction motor

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters
Motor Control Blockset / Electrical Systems / Motors



Description

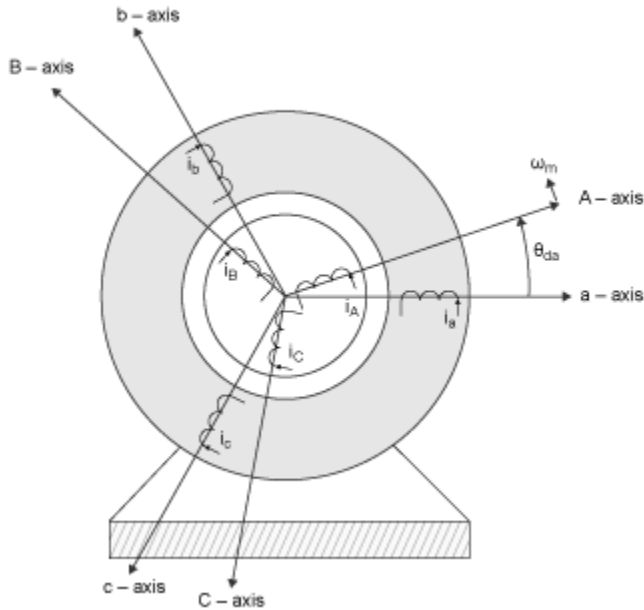
The Induction Motor block implements a three-phase induction motor. The block uses the three-phase input voltages to regulate the individual phase currents, allowing control of the motor torque or speed.

Note The block parameters use per-phase values of a star-equivalent induction motor.

By default, the block sets the **Simulation Type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

Three-Phase Sinusoidal Model Electrical System

The block implements equations that are expressed in a stationary rotor reference (qd) frame. The d-axis aligns with the a-axis. All quantities in the rotor reference frame are referred to the stator.



The block uses these equations to calculate the electrical speed (ω_{em}) and slip speed (ω_{slip}).

$$\omega_{em} = P\omega_m$$

$$\omega_{slip} = \omega_{syn} - \omega_{em}$$

To calculate the dq rotor electrical speed with respect to the rotor A-axis (dA), the block uses the difference between the stator a-axis (da) speed and slip speed:

$$\omega_{dA} = \omega_{da} - \omega_{em}$$

To simplify the equations for the flux, voltage, and current transformations, the block uses a stationary reference frame:

$$\omega_{da} = 0$$

$$\omega_{dA} = -\omega_{em}$$

Calculation	Equation
Flux	$\frac{d}{dt} \begin{bmatrix} \lambda_{sd} \\ \lambda_{sq} \end{bmatrix} = \begin{bmatrix} v_{sd} \\ v_{sq} \end{bmatrix} - R_s \begin{bmatrix} i_{sd} \\ i_{sq} \end{bmatrix} - \omega_{da} \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix} \begin{bmatrix} \lambda_{sd} \\ \lambda_{sq} \end{bmatrix}$ $\frac{d}{dt} \begin{bmatrix} \lambda_{rd} \\ \lambda_{rq} \end{bmatrix} = \begin{bmatrix} v_{rd} \\ v_{rq} \end{bmatrix} - R_r \begin{bmatrix} i_{rd} \\ i_{rq} \end{bmatrix} - \omega_{dA} \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix} \begin{bmatrix} \lambda_{rd} \\ \lambda_{rq} \end{bmatrix}$ $\begin{bmatrix} \lambda_{sd} \\ \lambda_{sq} \\ \lambda_{rd} \\ \lambda_{rq} \end{bmatrix} = \begin{bmatrix} L_s & 0 & L_m & 0 \\ 0 & L_s & 0 & L_m \\ L_m & 0 & L_r & 0 \\ 0 & L_m & 0 & L_r \end{bmatrix} \begin{bmatrix} i_{sd} \\ i_{sq} \\ i_{rd} \\ i_{rq} \end{bmatrix}$

Calculation	Equation
Current	$\begin{bmatrix} i_{sd} \\ i_{sq} \\ i_{rd} \\ i_{rq} \end{bmatrix} = \left(\frac{1}{L_m^2 - L_r L_s} \right) \begin{bmatrix} -L_r & 0 & L_m & 0 \\ 0 & -L_r & 0 & L_m \\ L_m & 0 & -L_s & 0 \\ 0 & L_m & 0 & -L_s \end{bmatrix} \begin{bmatrix} \lambda_{sd} \\ \lambda_{sq} \\ \lambda_{rd} \\ \lambda_{rq} \end{bmatrix}$
Inductance	$L_s = L_{ls} + L_m$ $L_r = L_{lr} + L_m$
Electromagnetic torque	$T_e = PL_m(i_{sq}i_{rd} - i_{sd}i_{rq})$
Power invariant dq transformation to ensure that the dq and three phase powers are equal	$\begin{bmatrix} v_{sd} \\ v_{sq} \end{bmatrix} = \sqrt{\frac{2}{3}}$ $\begin{bmatrix} \cos(\theta_{da}) & \cos(\theta_{da} - \frac{2\pi}{3}) & \cos(\theta_{da} + \frac{2\pi}{3}) \\ -\sin(\theta_{da}) & -\sin(\theta_{da} - \frac{2\pi}{3}) & -\sin(\theta_{da} + \frac{2\pi}{3}) \end{bmatrix} \begin{bmatrix} v_a \\ v_b \\ v_c \end{bmatrix}$ $\begin{bmatrix} i_a \\ i_b \\ i_c \end{bmatrix} = \sqrt{\frac{2}{3}} \begin{bmatrix} \cos(\theta_{da}) & -\sin(\theta_{da}) \\ \cos(\theta_{da} - \frac{2\pi}{3}) & -\sin(\theta_{da} - \frac{2\pi}{3}) \\ \cos(\theta_{da} + \frac{2\pi}{3}) & -\sin(\theta_{da} + \frac{2\pi}{3}) \end{bmatrix} \begin{bmatrix} i_{sd} \\ i_{sq} \end{bmatrix}$

The equations use these variables.

ω_m	Angular velocity of the rotor (rad/s)
ω_{em}	Electrical rotor speed (rad/s)
ω_{slip}	Electrical rotor slip speed (rad/s)
ω_{syn}	Synchronous rotor speed (rad/s)
ω_{da}	dq stator electrical speed with respect to the rotor a-axis (rad/s)
ω_{dA}	dq stator electrical speed with respect to the rotor A-axis (rad/s)
θ_{da}	dq stator electrical angle with respect to the rotor a-axis (rad)
θ_{dA}	dq stator electrical angle with respect to the rotor A-axis (rad)
L_q, L_d	q- and d-axis inductances (H)
L_s	Stator inductance (H)
L_r	Rotor inductance (H)
L_m	Magnetizing inductance (H)
L_{ls}	Stator leakage inductance (H)
L_{lr}	Rotor leakage inductance (H)
v_{sq}, v_{sd}	Stator q- and d-axis voltages (V)
i_{sq}, i_{sd}	Stator q- and d-axis currents (A)
$\lambda_{sq}, \lambda_{sd}$	Stator q- and d-axis flux (Wb)
i_{rq}, i_{rd}	Rotor q- and d-axis currents (A)

$\lambda_{rq}, \lambda_{rd}$	Rotor q- and d-axis flux (Wb)
v_a, v_b, v_c	Stator voltage phases a, b, c (V)
i_a, i_b, i_c	Stator currents phases a, b, c (A)
R_s	Resistance of the stator windings (Ohm)
R_r	Resistance of the rotor windings (Ohm)
P	Number of pole pairs
T_e	Electromagnetic torque (Nm)

Mechanical System

The motor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of motor and load (kgm ²)
F	Combined viscous friction of motor and load (N·m/(rad/s))
θ_m	Motor mechanical angular position (rad)
T_m	Motor shaft torque (Nm)
T_e	Electromagnetic torque (Nm)
T_f	Motor shaft static friction torque (Nm)
ω_m	Angular mechanical velocity of the motor (rad/s)

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	$P_{bus} = v_a i_a + v_b i_b + v_c i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	$P_{elec} = -(R_s i_{sd}^2 + R_s i_{sq}^2 + R_r i_{rd}^2 + R_r i_{rq}^2)$
	<ul style="list-style-type: none"> Positive signals indicate an input 			

Bus Signal		Description	Variable	Equations
	<ul style="list-style-type: none"> Negative signals indicate a loss 	PwrMech Loss	Mechanical power loss	P_{mech} When Port Configuration is set to Torque: $P_{mech} = -(\omega_m^2 F + \omega_m T_f)$ When Port Configuration is set to Speed: $P_{mech} = 0$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrMtrStored	Stored motor power	$P_{str} = P_{bus} + P_{mot} + P_{elec} + P_{mech}$

The equations use these variables.

R_s	Stator resistance (Ohm)
R_r	Motor resistance (Ohm)
i_a, i_b, i_c	Stator phase a, b, and c current (A)
i_{sq}, i_{sd}	Stator q- and d-axis currents (A)
v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage (V)
ω_m	Angular mechanical velocity of the rotor (rad/s)
F	Combined motor and load viscous damping (N·m/(rad/s))
T_e	Electromagnetic torque (Nm)
T_f	Combined motor and load friction torque (Nm)

Ports

Input

LdTrq — Load torque on motor

scalar

Load torque on the motor shaft, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port configuration** parameter.

Spd — Rotor shaft speed

scalar

Angular velocity of the rotor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port configuration** parameter.

PhaseVolt – Stator terminal voltages

1-by-3 array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Output

Info – Bus signal

bus

The bus signal contains these block calculations.

Signal		Description	Variable	Units	
IaStator		Stator phase current A	i_a	A	
IbStator		Stator phase current B	i_b	A	
IcStator		Stator phase current C	i_c	A	
IdSync		Direct axis current	i_d	A	
IqSync		Quadrature axis current	i_q	A	
VdSync		Direct axis voltage	v_d	V	
VqSync		Quadrature axis voltage	v_q	V	
MtrSpd		Angular mechanical velocity of the rotor	ω_m	rad/s	
MtrMechPos		Rotor mechanical angular position	θ_m	rad	
MtrPos		Rotor electrical angular position	θ_e	rad	
MtrTrq		Electromagnetic torque	T_e	N·m	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr – Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq – Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Port configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Port configuration** parameter.

Parameters**Block Options****Simulation type — Select simulation type**

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to Discrete.

Dependencies

Setting **Simulation Type** to Discrete creates the **Sample Time, Ts** parameter.

Sample time, Ts — Sample time for discrete integration

0.001 (default) | scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation Type** to Discrete creates the **Sample Time, Ts** parameter.

Port configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd
Speed	Spd	MtrTrq

Parameters**Number of pole pairs, P — Pole pairs**

2 (default) | scalar

Motor pole pairs, P .

Stator resistance and leakage inductance, Zs — Resistance and inductance

[1.77 0.0139] (default) | vector

Stator resistance, R_s , in ohms and leakage inductance, L_{ls} , in H.

Rotor resistance and leakage inductance, Zr — Resistance and inductance

[1.34 0.0121] (default) | vector

Rotor resistance, R_r , in ohms and leakage inductance, L_{lr} , in H.**Magnetizing inductance, Lm — Inductance**

0.3687 (default) | scalar

Magnetizing inductance, L_m , in H.**Physical inertia, viscous damping, static friction, mechanical — Inertia, damping, friction**

[0.001 0 0] (default) | vector

Mechanical properties of the rotor:

- Inertia, J , in $\text{kg}\cdot\text{m}^2$
- Viscous damping, F , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction, T_f , in $\text{N}\cdot\text{m}$

DependenciesTo enable this parameter, select Torque for the **Port configuration**.**Initial Values****Initial mechanical position, theta_init — Angular position**

0 (default) | scalar

Initial rotor angular position, θ_{m0} , in rad.**Initial mechanical speed, omega_init — Angular speed**

0 (default) | scalar

Initial angular velocity of the rotor, ω_{m0} , in rad/s.**Dependencies**To enable this parameter, select Torque for the **Port configuration**.

Version History

Introduced in R2017a

References

- [1] Mohan, Ned. *Advanced Electric Drives: Analysis, Control and Modeling Using Simulink*. Minneapolis, MN: MNPETE, 2001.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

[IM Controller](#) | [Flux-Based PMSM](#) | [Interior PMSM](#) | [Mapped Motor](#) | [Surface Mount PMSM](#)

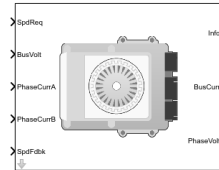
Topics

[“Estimate Motor Parameters Using Motor Control Blockset Parameter Estimation Tool” \(Motor Control Blockset\)](#)

IM Controller

Internal torque-based, field-oriented controller for an induction motor with an optional outer-loop speed controller

Library: Powertrain Blockset / Propulsion / Electric Motor Controllers

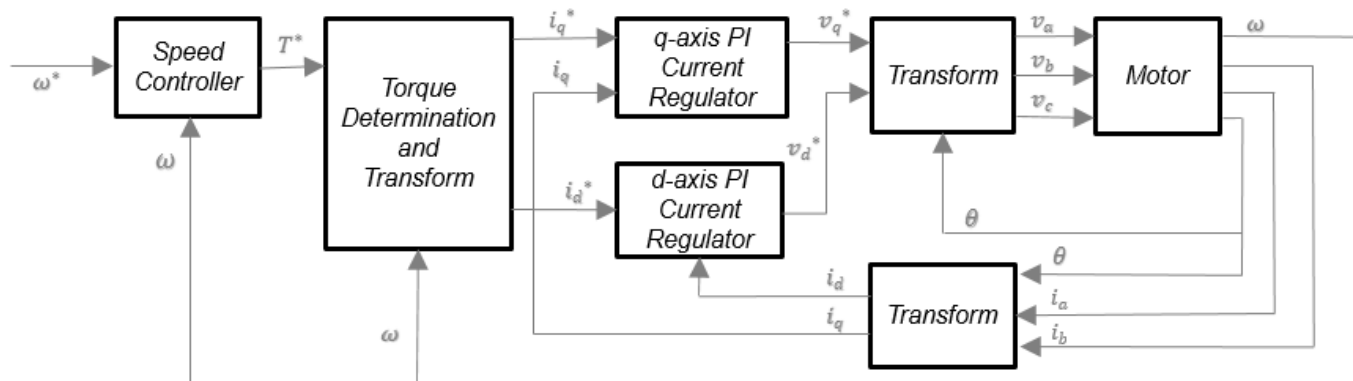


Description

The IM Controller block implements an internal torque-based, field-oriented controller for an induction motor (IM) with an optional outer-loop speed controller. The torque control implements a strategy to control the motor flux. You can specify either speed or torque control.

The IM Controller implements equations for speed control, torque determination, regulators, transforms, and motors.

The figure illustrates the information flow in the block.



The block implements equations that use these variables.

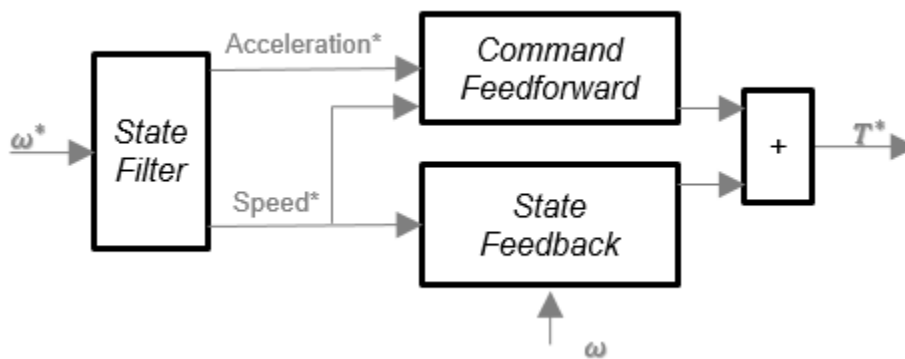
ω	Rotor speed
ω^*	Rotor speed command
T^*	Torque command
i_d	d-axis current
i_d^*	d-axis current command
i_q	q-axis current
i_q^*	q-axis current command

v_d	d-axis voltage
v_d^*	d-axis voltage command
v_q	q-axis voltage
v_q^*	q-axis voltage command
v_a, v_b, v_c	Stator phase a, b, c voltages
i_a, i_b, i_c	Stator phase a, b, c currents

Speed Controller

To implement the speed controller, select the **Control Type** parameter `Speed Control`. If you select the **Control Type** parameter `Torque Control`, the block does not implement the speed controller.

The speed controller determines the torque command by implementing a state filter, and calculating the feedforward and feedback commands. If you do not implement the speed controller, input a torque command to the IM Controller block.



State Filter

The state filter is a low-pass filter that generates the acceleration command based on the speed command. On the **Speed Controller** tab:

- To make the speed-command lag time negligible, specify a **Bandwidth of the state filter** parameter.
- To calculate a **Speed regulation time constant, Ksf** gain based on the state filter bandwidth, select **Calculate Speed Regulator Gains**.

The discrete form of characteristic equation is given by:

$$z + K_{sf}T_{sm} - 1$$

The filter calculates the gain using this equation.

$$K_{sf} = \frac{1 - \exp(-T_{sm}2\pi EV_{sf})}{T_{sm}}$$

The equation uses these variables.

EV_{sf}	Bandwidth of the speed command filter
T_{sm}	Motion controller sample time
K_{sf}	Speed regulator time constant

State Feedback

To generate the state feedback torque, the block uses the filtered speed error signal from the state filter. The feedback torque calculation also requires gains for speed regulator.

On the **Speed Controller** tab, select **Calculate Speed Regulator Gains** to compute:

- **Proportional gain, b_a**
- **Angular gain, K_{sa}**
- **Rotational gain, K_{isa}**

For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value on the **Motor Parameter** tab.

The gains for the state feedback are calculated using these equations.

Calculation	Equations
Discrete forms of characteristic equation	$z^3 + \frac{(-3J_p + T_s b_a + T_s^2 K_{sa} + T_s^3 K_{isa})}{J_p} z^2 + \frac{(3J_p - 2T_s b_a - T_s^2 K_{sa})}{J_p} z + \frac{-J_p + T_s b_a}{J_p}$ $(z - p_1)(z - p_2)(z - p_3) = z^3 + (p_1 + p_2 + p_3)z^2 + (p_1 p_2 + p_2 p_3 + p_1 p_3)z^2 - p_1 p_2 p_3$
Speed regulator proportional gain	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$
Speed regulator integral gain	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$
Speed regulator double integral gain	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
J_p	Motor inertia
T_{sm}	Motion controller sample time

Command Feedforward

To generate the state feedforward torque, the block uses the filtered speed and acceleration from the state filter. Also, the feedforward torque calculation uses the inertia, viscous damping, and static friction. To achieve zero tracking error, the torque command is the sum of the feedforward and feedback torque commands.

Selecting **Calculate Speed Regulator Gains** on the **Speed Controller** tab updates the inertia, viscous damping, and static friction with the **Physical inertia, viscous damping, static friction** parameter values on the **Motor Parameter** tab.

The feedforward torque command uses this equation.

$$T_{cmd_ff} = J_p \dot{\omega}_m + F_v \omega_m + F_s \frac{\omega_m}{|\omega_m|}$$

The equation uses these variables.

J_p	Motor inertia
T_{cmd_ff}	Torque command feedforward
F_s	Static friction torque constant
F_v	Viscous friction torque constant
F_s	Static friction torque constant
ω_m	Rotor mechanical speed

Torque Determination

The block uses a quadrature current to determine the base speed and the current commands. The motor ratings determine the rated electrical speed.

Calculation	Equations
Current commands	$i_{qref} = \frac{T_{cmd}}{i_{sq_0} \cdot P \cdot \left(\frac{L_m^2}{L_r}\right)}$ <p>If $\omega_e \leq \omega_{rated}$ $i_{dref} = i_{sd_0}$ Else $i_{dref} = \frac{i_{sd_0} \cdot \omega_{rated}}{ \omega_e }$ End</p>
Inductance	$L_r = L_{lr} + L_m$ $L_s = L_{ls} + L_m$

The equations use these variables.

i_{dref}	d-axis reference current
i_{qref}	q-axis reference current
i_{sd_0}	d-axis rated current
i_{sq_0}	q-axis rated current
ω_e	Rotor electrical speed
ω_{rated}	Rated electrical speed
L_{lr}	Rotor leaking inductance

L_r	Rotor winding inductance
L_{ls}	Stator leaking inductance
L_s	Stator winding inductance
L_m	Motor magnetizing inductance
P	Motor pole pairs
T_{cmd}	Commanded motor maximum torque

Current Regulators

The block regulates the current with an anti-windup feature. Classic proportional-integrator (PI) current regulators do not consider the d-axis and q-axis coupling or the back-electromagnetic force (EMF) coupling. As a result, transient performance deteriorates. To account for the coupling, the block implements the complex vector current regulator (CVCR) in the scalar format of the rotor reference frame. The CVCR decouples:

- d-axis and q-axis current cross-coupling
- Back-EMF cross-coupling

The current frequency response is a first-order system, with a bandwidth of $EV_{current}$.

The block implements these equations.

Calculation	Equations
Motor voltage, in the stator reference frame	$\sigma = 1 - \frac{L_m^2}{L_s L_r}$ $v_{sd} = R_s i_{sd} + \sigma L_s \frac{di_{sd}}{dt} + \frac{L_m}{L_r} \frac{d\lambda_{rd}}{dt} - P\omega_m \sigma L_s i_{sq}$ $v_{sq} = R_s i_{sq} + \sigma L_s \frac{di_{sq}}{dt} + \omega_d \frac{L_m}{L_r} \frac{d\lambda_{rd}}{dt} + P\omega_m \sigma L_s i_{sd}$
Current regulator gains	$\omega_b = 2\pi EV_{current}$ $K_p = \sigma L_d \omega_b$ $K_i = R_s \omega_b$
Transfer functions	$\frac{i_d}{i_{dref}} = \frac{\omega_b}{s + \omega_b}$ $\frac{i_q}{i_{qref}} = \frac{\omega_b}{s + \omega_b}$

The equations use these variables.

$EV_{current}$	Current regulator bandwidth
i_d	d-axis current
i_q	q-axis current
i_{sq}	Stator q-axis current
i_{sd}	Stator d-axis current
v_{sd}	Stator d-axis voltage

v_{sq}	Stator q-axis voltage
K_p	Current regulator d-axis gain
K_i	Current regulator integrator gain
L_s	Stator winding inductance
L_m	Motor magnetizing inductance
L_r	Rotor winding inductance
R_s	Stator phase winding resistance
λ_{rd}	Rotor d-axis magnetic flux
σ	Leakage factor
p	Motor pole pairs

Transforms

To calculate the voltages and currents in balanced three-phase (a, b) quantities, quadrature two-phase (α, β) quantities, and rotating (d, q) reference frames, the block uses the Clarke and Park Transforms.

In the transform equations.

$$\omega_e = P\omega_m$$

$$\frac{d\theta_e}{dt} = \omega_e$$

Transform	Description	Equations
Clarke	Converts balanced three-phase quantities (a, b) into balanced two-phase quadrature quantities (α, β).	$x_\alpha = \frac{2}{3}x_a - \frac{1}{3}x_b - \frac{1}{3}x_c$ $x_\beta = \frac{\sqrt{3}}{2}x_b - \frac{\sqrt{3}}{2}x_c$
Park	Converts balanced two-phase orthogonal stationary quantities (α, β) into an orthogonal rotating reference frame (d, q).	$x_d = x_\alpha \cos\theta_e + x_\beta \sin\theta_e$ $x_q = -x_\alpha \sin\theta_e + x_\beta \cos\theta_e$
Inverse Clarke	Converts balanced two-phase quadrature quantities (α, β) into balanced three-phase quantities (a, b).	$x_a = x_\alpha$ $x_b = -\frac{1}{2}x_\alpha + \frac{\sqrt{3}}{2}x_\beta$ $x_c = -\frac{1}{2}x_\alpha - \frac{\sqrt{3}}{2}x_\beta$
Inverse Park	Converts an orthogonal rotating reference frame (d, q) into balanced two-phase orthogonal stationary quantities (α, β).	$x_\alpha = x_d \cos\theta_e - x_q \sin\theta_e$ $x_\beta = x_d \sin\theta_e + x_q \cos\theta_e$

The transforms use these variables.

ω_m	Rotor mechanical speed
P	Motor pole pairs
ω_e	Rotor electrical speed

θ_e Rotor electrical angle
 x Phase current or voltage

Motor

The block uses the phase currents and phase voltages to estimate the DC bus current. Positive current indicates battery discharge. Negative current indicates battery charge. The block uses these equations.

Load power	$Ld_{Pwr} = v_a i_a + v_b i_b + v_c i_c$
Source power	$Src_{Pwr} = Ld_{Pwr} + Pwr_{Loss}$
DC bus current	$i_{bus} = \frac{Src_{Pwr}}{v_{bus}}$
Estimated rotor torque	$MtrTrq_{est} = P \lambda_{rd} i_{sq} \frac{L_m}{L_r}$
Power loss for single efficiency source to load	$Pwr_{Loss} = \frac{100 - Eff}{Eff} \cdot Ld_{Pwr}$
Power loss for single efficiency load to source	$Pwr_{Loss} = \frac{100 - Eff}{100} \cdot Ld_{Pwr} $
Power loss for tabulated efficiency	$Pwr_{Loss} = f(\omega_m, MtrTrq_{est})$

The equations use these variables.

v_a, v_b, v_c Stator phase a, b, c voltages
 v_{bus} Estimated DC bus voltage
 i_a, i_b, i_c Stator phase a, b, c currents
 i_{bus} Estimated DC bus current
 Eff Overall inverter efficiency
 ω_m Rotor mechanical speed
 L_r Rotor winding inductance
 L_m Motor magnetizing inductance
 λ_{rd} Rotor d-axis magnetic flux
 i_{sq} q-axis current
 P Motor pole pairs

Electrical Losses

To specify the electrical losses, on the **Electrical Losses** tab, for **Parameterize losses by**, select one of these options.

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.

Setting	Block Implementation
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> • Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. • Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. • Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. • Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use Tabulated loss data instead of Tabulated efficiency data:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Ports

Input

SpdReq — Rotor mechanical speed command

scalar

Rotor mechanical speed command, ω_m^* , in rad/s.

Dependencies

To create this port, select Speed Control for the **Control Type** parameter.

TrqCmd — Torque command

scalar

Torque command, T^* , in N·m.

Dependencies

To create this port, select Torque Control for the **Control Type** parameter.

BusVolt — DC bus voltage

scalar

DC bus voltage v_{bus} , in V.

PhaseCurrA — Current

scalar

Stator current phase a, i_a , in A.

PhaseCurrB — Current

scalar

Stator current phase b, i_b , in A.

SpdFdbk – Rotor mechanical speed

scalar

Rotor mechanical speed, ω_m , in rad/s.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
SrcPwr	Source power	W
LdPwr	Load power	W
PwrLoss	Power loss	W
MtrTrqEst	Estimated motor torque	N·m

BusCurr – Bus current

scalar

Estimated DC bus current, i_{bus} , in A.

PhaseVolt – Stator terminal voltages

array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Parameters

Block Options

Control Type – Select control

Speed Control (default) | Torque Control

If you select Torque Control, the block does not implement the speed controller.

This table summarizes the port configurations.

Port Configuration	Creates Ports
Speed Control	SpdReq
Torque Control	TrqCmd

Motor

Stator resistance, Rs – Resistance

1.77 (default) | scalar

Stator phase winding resistance, R_s , in ohm.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Stator resistance, R_s	D-axis rated current, I_{sd_0}	Id and Iq Calculation
	Q-axis rated current, I_{sq_0}	
	Torque at rated current, T_{em}	
	D and Q axis integral gain, K_i	Current Controller

Stator leakage inductance, L_{ls} – Inductance

0.0139 (default) | scalar

Stator leakage inductance, L_{ls} , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Stator leakage inductance, L_{ls}	D-axis rated current, I_{sd_0}	Id and Iq Calculation
	Q-axis rated current, I_{sq_0}	
	Torque at rated current, T_{em}	
	D and Q axis proportional gain, K_p	Current Controller
	D and Q axis integral gain, K_i	

Rotor resistance, R_r – Resistance

1.34 (default) | scalar

Rotor resistance, R_r , in ohm.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rotor resistance, R_r	D-axis rated current, I_{sd_0}	Id and Iq Calculation
	Q-axis rated current, I_{sq_0}	
	Torque at rated current, T_{em}	

Rotor leakage inductance, L_{lr} – Inductance

0.0121 (default) | scalar

Rotor leakage inductance, L_{lr} , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rotor leakage inductance, Llr	D-axis rated current, Isd_0	Id and Iq Calculation
	Q-axis rated current, Isq_0	
	Torque at rated current, Tem	
	D and Q axis proportional gain, Kp	Current Controller

Rotor magnetizing inductance, Lm – Inductance

0.3687 (default) | scalar

Rotor magnetizing inductance, L_m , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rotor leakage inductance, Llr	D-axis rated current, Isd_0	Id and Iq Calculation
	Q-axis rated current, Isq_0	
	Torque at rated current, Tem	
	D and Q axis proportional gain, Kp	Current Controller

Number of pole pairs, PolePairs – Poles

2 (default) | scalar

Motor pole pairs, P .

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rotor leakage inductance, Llr	Torque at rated current, Tem	Id and Iq Calculation

Physical inertia, viscous damping, static friction, Mechanical – Mechanical properties of motor

[0.025, 0, 0] (default) | vector

Mechanical properties of the motor:

- Motor inertia, F_v , in kgm^2
- Viscous friction torque constant, F_v , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction torque constant, F_s , in $\text{N}\cdot\text{m}$

Dependencies

To enable this parameter, set the **Control Type** parameter to Speed Control.

For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value that is on the **Motor Parameters** tab.

Parameter	Used to Derive	
	Parameter	Tab
Physical inertia, viscous damping, static friction, Mechanical	Proportional gain, ba Angular gain, Ksa Rotational gain, Kisa Inertia compensation, Jcomp Viscous damping compensation, Fv Static friction, Fs	Speed Controller

Id and Iq Calculation

Rated synchronous speed, F_{rate} – Motor frequency

60 (default) | scalar

Motor-rated electrical frequency, F_{rate} , in Hz.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rated synchronous speed, F_{rate}	D-axis rated current, Isd_0 Q-axis rated current, Isq_0 Torque at rated current, Tem	Id and Iq Calculation

Rated line to line voltage RMS, V_{rate} – Motor voltage

460 (default) | scalar

Motor-rated line-to-line voltage, V_{rate} , in V.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rated synchronous speed, F_{rate}	D-axis rated current, I_{sd_0}	Id and Iq Calculation
	Q-axis rated current, I_{sq_0}	
	Torque at rated current, T_{em}	

Rated slip, S_{rate} – Motor slip speed

0.0172 (default) | scalar

Motor-rated slip speed, S_{rate} , dimensionless.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Rated slip, S_{rate}	D-axis rated current, I_{sd_0}	Id and Iq Calculation
	Q-axis rated current, I_{sq_0}	
	Torque at rated current, T_{em}	

Calculate Rated Stator Flux Current – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Id and Iq Calculation** tab, when you select **Calculate Rated Stator Flux Current**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
D-axis rated current, I_{sd_0} Q-axis rated current, I_{sq_0} Torque at rated current, T_{em}	Rated synchronous speed, F_{rate}	Id and Iq Calculation
	Rated line to line voltage RMS, V_{rate}	
	Rated slip, S_{rate}	

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
	Stator resistance, Rs Stator leakage inductance, Lls Rotor resistance, Rr Rotor leakage inductance, Llr Rotor magnetizing inductance, Lm	Motor Parameters

D-axis rated current, Isd_0 – Derived

3.1004 (default) | scalar

Derived d-axis rated current, in A.

Dependencies

On the **Id and Iq Calculation** tab, when you select **Calculate Rated Stator Flux Current**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
D-axis rated current, Isd_0	Rated synchronous speed, Frate	Id and Iq Calculation
Q-axis rated current, Isq_0	Rated line to line voltage RMS, Vrate	
Torque at rated current, Tem	Rated slip, Srate	
	Stator resistance, Rs Stator leakage inductance, Lls Rotor resistance, Rr Rotor leakage inductance, Llr Rotor magnetizing inductance, Lm	Motor Parameters

Q-axis rated current, Isq_0 – Derived

5.7131 (default) | scalar

Derived q-axis rated current, in A.

Dependencies

On the **Id and Iq Calculation** tab, when you select **Calculate Rated Stator Flux Current**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
D-axis rated current, Isd_0	Rated synchronous speed, Frate	Id and Iq Calculation
Q-axis rated current, Isq_0	Rated line to line voltage RMS, Vrate	
Torque at rated current, Tem	Rated slip, Srate	
	Stator resistance, Rs	Motor Parameters
	Stator leakage inductance, Lls	
	Rotor resistance, Rr	
	Rotor leakage inductance, Llr	
	Rotor magnetizing inductance, Lm	

Torque at rated current, Tem – Derived

12.6467 (default) | scalar

Torque at rated current, in N·m.

Dependencies

On the **Id and Iq Calculation** tab, when you select **Calculate Rated Stator Flux Current**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
D-axis rated current, Isd_0	Rated synchronous speed, Frate	Id and Iq Calculation
Q-axis rated current, Isq_0	Rated line to line voltage RMS, Vrate	
Torque at rated current, Tem	Rated slip, Srate	

Derived Parameter on Id and Iq Calculation tab	Dependency	
	Parameter	Tab
	Stator resistance, Rs Stator leakage inductance, Lls Rotor resistance, Rr Rotor leakage inductance, Llr Rotor magnetizing inductance, Lm	Motor Parameters

Current Controller

Bandwidth of the current regulator, EV_current – Bandwidth

200 (default) | scalar

Current regulator bandwidth, in Hz.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the current regulator, EV_current	D and Q axis integral gain, Ki D and Q axis proportional gain, Kp	Current Controller

Sample time for the torque control, Tst – Time

5e-5 (default) | scalar

Torque control sample time, in s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Sample time for the torque control, Tst	Speed regulation time constant, Ksf	Speed Controller

Calculate Current Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Current Controller** tab, when you select **Calculate Current Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Current Controller tab	Dependency	
	Parameter	Tab
D and Q axis proportional gain, Kp	Bandwidth of the current regulator, EV_current	Current Controller
	Stator resistance, Rs	Motor Parameters
D and Q axis integral gain, Ki	Stator leakage inductance, Lls	
	Rotor resistance, Rr	
	Rotor leakage inductance, Llr	
	Rotor magnetizing inductance, Lm	

D and Q axis proportional gain, Kp – Derived

32.1894 (default) | scalar

Derived proportional gain, in V/A.

Dependencies

On the **Current Controller** tab, when you select **Calculate Current Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Current Controller tab	Dependency	
	Parameter	Tab
D and Q axis proportional gain, Kp	Bandwidth of the current regulator, EV_current	Current Controller
	Stator resistance, Rs	Motor Parameters
D and Q axis integral gain, Ki	Stator leakage inductance, Lls	
	Rotor resistance, Rr	
	Rotor leakage inductance, Llr	
	Rotor magnetizing inductance, Lm	

D and Q axis integral gain, Ki – Derived

2224.2476 (default) | scalar

Derived integral gain, in V/A*s.

Dependencies

On the **Current Controller** tab, when you select **Calculate Current Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Current Controller tab	Dependency	
	Parameter	Tab
D and Q axis proportional gain, Kp	Bandwidth of the current regulator, EV_current	Current Controller
	Stator resistance, Rs	Motor Parameters
D and Q axis integral gain, Ki	Stator leakage inductance, Lls	
	Rotor resistance, Rr	
	Rotor leakage inductance, Llr	
	Rotor magnetizing inductance, Lm	

Speed Controller

Bandwidth of the motion controller, EV_motion – Bandwidth

[20, 4, 0.8] (default) | vector

Motion controller bandwidth, in Hz. Set the first element of the vector to the desired cutoff frequency. Set the second and third elements of the vector to the higher-order cut off frequencies. You can set the value of the next element to 1/5 the value of the previous element. For example, if the desired cutoff frequency is 20 Hz, specify [20 4 0.8].

Dependencies

The parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the motion controller, EV_motion	Proportional gain, ba	Speed Controller
	Angular gain, Ksa	
	Rotational gain, Kisa	

Bandwidth of the state filter, EV_sf – Bandwidth

200 (default) | scalar

State filter bandwidth, in Hz.

Dependencies

The parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the state filter, EV_sf	Speed regulation time constant, Ksf	Speed Controller

Calculate Speed Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Speed Controller** tab, when you select **Calculate Speed Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Speed Controller tab		Depends On	
		Parameter	Tab
Proportional gain, ba	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$	Bandwidth of the motion controller, EV_motion Bandwidth of the state filter, EV_sf	Speed Controller
Angular gain, Ksa	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$	Sample time for the torque control, Tst	Current Controller
Rotational gain, Kisa	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
Speed regulation time constant, Ksf	$K_{sf} = \frac{1 - \exp(-T_{sm} 2\pi EV_{sf})}{T_{sm}}$		
Inertia compensation, Jcomp	$J_{comp} = J_p$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
Viscous damping compensation, Fv	F_v		
Static friction, Fs	F_s		

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
K_{sf}	Speed regulator time constant
J_p	Motor inertia
EV_{sf}	State filter bandwidth
EV_{motion}	Motion controller bandwidth

Proportional gain, b_a – Derived

3.7477 (default) | scalar

Derived proportional gain, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Proportional gain, b_a	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_{motion}	Speed Controller

Angular gain, K_{sa} – Derived

94.0877 (default) | scalar

Derived angular gain, in N·m/rad.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Angular gain, K_{sa}	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_{motion}	Speed Controller

Rotational gain, K_{isa} – Derived

381.7822 (default) | scalar

Derived rotational gain, in N·m/(rad*s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Rotational gain, Kisa	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_motion	Speed Controller

Speed regulation time constant, Ksf – Derived

1217.9727 (default) | scalar

Derived speed regulation time constant, in 1/s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Speed regulation time constant, Ksf	Sample time for the torque control, Tst	Current Controller
	Bandwidth of the state filter, EV_sf	Speed Controller

Inertia compensation, Jcomp – Derived

0.025 (default) | scalar

Derived inertia compensation, in kg·m².

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Inertia compensation, Jcomp	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Viscous damping compensation, Fv – Derived

0 (default) | scalar

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Viscous damping compensation, F_v	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Static friction, F_s – Derived

0 (default) | scalar

Derived static friction, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Static friction, F_s	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Electrical Losses

Parameterize losses by – Select type

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use Tabulated loss data instead of Tabulated efficiency data:

- Efficiency becomes ill defined for zero speed or zero torque.

- You can account for fixed losses that are still present for zero speed or torque.

Overall inverter efficiency, eff – Constant

98 (default) | scalar

Overall inverter efficiency, Eff , in %.**Dependencies**To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.**Vector of speeds (w) for tabulated loss, w_loss_bp – Breakpoints**

[0 200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating losses, in rad/s.

DependenciesTo enable this parameter, for **Parameterize losses by**, select Tabulated loss data.**Vector of torques (T) for tabulated loss, T_loss_bp – Breakpoints**

[0 25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating losses, in N·m.

DependenciesTo enable this parameter, for **Parameterize losses by**, select Tabulated loss data.**Corresponding losses, $losses_table$ – Table**

[100 100 100 100 100;100 150 200 250 300;100 200 300 400 500;100 250 400 550 700;100 300 500 700 900;100 350 600 850 1100] (default) | M-by-N array

Array of values for electrical losses as a function of M speeds and N torques, in W. Each value specifies the losses for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

DependenciesTo enable this parameter, for **Parameterize losses by**, select Tabulated loss data.**Vector of speeds (w) for tabulated efficiency, w_eff_bp – Breakpoints**

[200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating efficiency, in rad/s.

DependenciesTo enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.**Vector of torques (T) for tabulated efficiency, T_eff_bp – Breakpoints**

[25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating efficiency, in N·m.

DependenciesTo enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Corresponding efficiency, efficiency_table — Table

[96.2 98.1 98.7 99;98.1 99 99.4 99.5;98.7 99.4 99.6 99.7;99 99.5 99.7 99.8;99.2 99.6 99.7 99.8] (default) | M-by-N array

Array of efficiency as a function of M speeds and N torque, in %. Each value specifies the efficiency for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Version History

Introduced in R2017a

References

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- [2] Shigeo Morimoto, Masayuka Sanada, Yoji Takeda. "Wide-speed operation of interior permanent magnet synchronous motors with high-performance current regulator." *IEEE Transactions on Industry Applications*, Vol. 30, Issue 4, July/August 1994, pp. 920-926.
- [3] Muyang Li. *Flux-Weakening Control for Permanent-Magnet Synchronous Motors Based on Z-Source Inverters*. Master's Thesis, Marquette University, e-Publications@Marquette, Fall 2014.
- [4] Briz, Fernando, Michael W. Degner, and Robert D. Lorenz. "Analysis and design of current regulators using complex vectors." *IEEE Transactions on Industry Applications*, Vol. 36, Issue 3, May/June 2000, pp. 817-825.
- [5] Briz, Fernando, et al. "Current and flux regulation in field-weakening operation [of induction motors]." *IEEE Transactions on Industry Applications*, Vol. 37, Issue 1, Jan/Feb 2001, pp. 42-50.
- [6] Mohan, Ned. *Advanced Electric Drives: Analysis, Control and Modeling Using Simulink*. Minneapolis, MN: MNPETE, 2001.

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

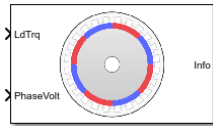
See Also

Induction Motor | Flux-Based PM Controller | Interior PM Controller | Surface Mount PM Controller

Surface Mount PMSM

Three-phase exterior permanent magnet synchronous motor with sinusoidal back electromotive force

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters
Motor Control Blockset / Electrical Systems / Motors



Description

The Surface Mount PMSM block implements a three-phase exterior permanent magnet synchronous motor (PMSM) with sinusoidal back electromotive force. The block uses the three-phase input voltages to regulate the individual phase currents, allowing the control of the motor torque or speed.

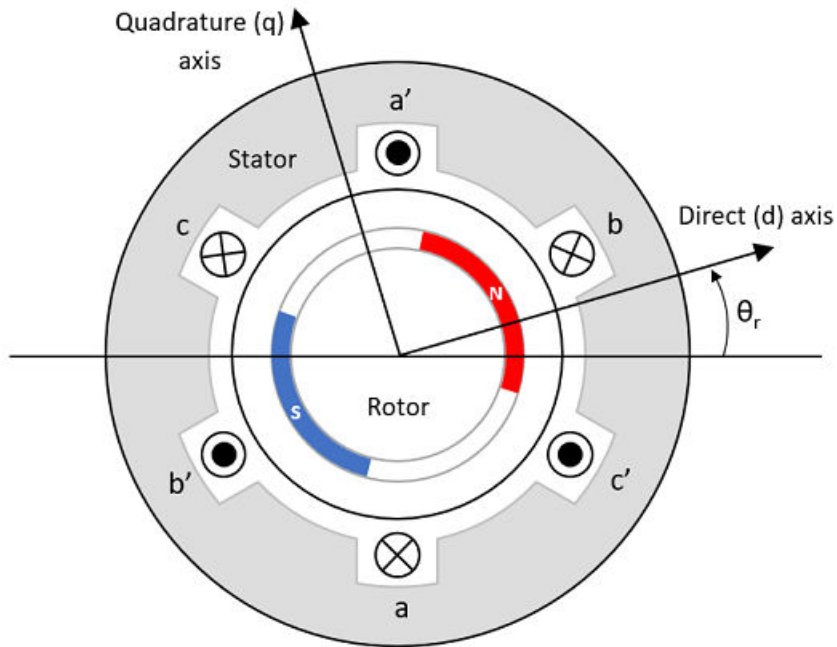
By default, the block sets the **Simulation type** parameter to **Continuous** to use a continuous sample time during simulation. If you want to generate code for fixed-step double- and single-precision targets, considering setting the parameter to **Discrete**. Then specify a **Sample Time, Ts** parameter.

On the **Parameters** tab, if you select **Back-emf** or **Torque constant**, the block implements one of these equations to calculate the permanent flux linkage constant.

Setting	Equation
Back-emf	$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$
Torque constant	$\lambda_{pm} = \frac{2}{3} \cdot \frac{K_t}{P}$

Motor Construction

This figure shows the motor construction with a single pole pair on the motor.



The motor magnetic field due to the permanent magnets creates a sinusoidal rate of change of flux with motor angle.

For the axes convention, the *a*-phase and permanent magnet fluxes are aligned when motor angle θ_r is zero.

Three-Phase Sinusoidal Model Electrical System

The block implements these equations, expressed in the motor flux reference frame (dq frame). All quantities in the motor reference frame are referred to the stator.

$$\omega_e = P\omega_m$$

$$\frac{d}{dt}i_d = \frac{1}{L_d}v_d - \frac{R}{L_d}i_d + \frac{L_q}{L_d}P\omega_m i_q$$

$$\frac{d}{dt}i_q = \frac{1}{L_q}v_q - \frac{R}{L_q}i_q - \frac{L_d}{L_q}P\omega_m i_d - \frac{\lambda_{pm}P\omega_m}{L_q}$$

$$T_e = 1.5P[\lambda_{pm}i_q + (L_d - L_q)i_d i_q]$$

The L_q and L_d inductances represent the relation between the phase inductance and the motor position due to the saliency of the motor magnets. For the surface mount PMSM, $L_d = L_q$.

The equations use these variables.

L_q, L_d	q- and d-axis inductances (H)
R	Resistance of the stator windings (ohm)
i_q, i_d	q- and d-axis currents (A)
v_q, v_d	q- and d-axis voltages (V)

ω_m	Angular mechanical velocity of the motor (rad/s)
ω_e	Angular electrical velocity of the motor (rad/s)
λ_{pm}	Permanent magnet flux linkage (Wb)
K_e	Back electromotive force (EMF) (Vpk_LL/krpm, where Vpk_LL is the peak voltage line-to-line measurement)
K_t	Torque constant (N·m/A)
P	Number of pole pairs
T_e	Electromagnetic torque (Nm)
Θ_e	Electrical angle (rad)

Mechanical System

The motor angular velocity is given by:

$$\frac{d}{dt}\omega_m = \frac{1}{J}(T_e - T_f - F\omega_m - T_m)$$

$$\frac{d\theta_m}{dt} = \omega_m$$

The equations use these variables.

J	Combined inertia of motor and load (kgm ²)
F	Combined viscous friction of motor and load (N·m/(rad/s))
θ_m	Motor mechanical angular position (rad)
T_m	Motor shaft torque (Nm)
T_e	Electromagnetic torque (Nm)
T_f	Motor shaft static friction torque (Nm)
ω_m	Angular mechanical velocity of the motor (rad/s)

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrMtr	Mechanical power	$P_{mot} = -\omega_m T_e$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrBus	Electrical power	$P_{bus} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrElecLoss	Resistive power loss	$P_{elec} = -\frac{3}{2}(R_s i_{sd}^2 + R_s i_{sq}^2)$

Bus Signal		Description	Variable	Equations
<ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrMech Loss	Mechanical power loss	P_{mech}	When Port Configuration is set to Torque: $P_{mech} = - (\omega_m^2 F + \omega_m T_f)$ When Port Configuration is set to Speed: $P_{mech} = 0$
PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrMtrStored	Stored motor power	P_{str}	$P_{str} = P_{bus} + P_{mot} + P_{elec} + P_{mech}$

The equations use these variables.

R_s	Stator resistance (ohm)
i_a, i_b, i_c	Stator phase a, b, and c current (A)
i_{sq}, i_{sd}	Stator q- and d-axis currents (A)
v_{an}, v_{bn}, v_{cn}	Stator phase a, b, and c voltage (V)
ω_m	Angular mechanical velocity of the motor (rad/s)
F	Combined motor and load viscous damping N·m/(rad/s)
T_e	Electromagnetic torque (Nm)
T_f	Combined motor and load friction torque (Nm)

Ports

Input

LdTrq — Load torque on motor

scalar

Load torque on the motor shaft, T_m , in N·m.

Dependencies

To create this port, select Torque for the **Port Configuration** parameter.

Spd — Motor shaft speed

scalar

Angular velocity of the motor, ω_m , in rad/s.

Dependencies

To create this port, select Speed for the **Port Configuration** parameter.

PhaseV_{olt} – Stator terminal voltages

1-by-3 array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Output**Info – Bus signal**

bus

The bus signal contains these block calculations.

Signal		Description	Variable	Units	
IaStator		Stator phase current A	i_a	A	
IbStator		Stator phase current B	i_b	A	
IcStator		Stator phase current C	i_c	A	
IdSync		Direct axis current	i_d	A	
IqSync		Quadrature axis current	i_q	A	
VdSync		Direct axis voltage	v_d	V	
VqSync		Quadrature axis voltage	v_q	V	
MtrSpd		Angular mechanical velocity of the motor	ω_m	rad/s	
MtrPos		Motor mechanical angular position	θ_m	rad	
MtrTrq		Electromagnetic torque	T_e	N·m	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	W
		PwrBus	Electrical power	P_{bus}	W
	PwrNotTrnsfrd	PwrElecLoss	Resistive power loss	P_{elec}	W
		PwrMechLoss	Mechanical power loss	P_{mech}	W
	PwrStored	PwrMtrStored	Stored motor power	P_{str}	W

PhaseCurr – Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq – Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

Dependencies

To create this port, select Speed for the **Mechanical input configuration** parameter.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

Dependencies

To create this port, select Torque for the **Mechanical input configuration** parameter.

Parameters

Block Options

Mechanical input configuration — Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Input Port	Creates Output Port
Torque	LdTrq	MtrSpd
Speed	Spd	MtrTrq

Simulation type — Select simulation type

Continuous (default) | Discrete

By default, the block uses a continuous sample time during simulation. If you want to generate code for single-precision targets, considering setting the parameter to Discrete.

Dependencies

Setting **Simulation type** to Discrete creates the **Sample Time, Ts** parameter.

Sample Time (Ts) — Sample time for discrete integration

0.001 (default) | scalar

Integration sample time for discrete simulation, in s.

Dependencies

Setting **Simulation type** to Discrete creates the **Sample Time, Ts** parameter.

Parameters

Number of pole pairs (P) — Pole pairs

4 (default) | scalar

Motor pole pairs, P .

Stator phase resistance per phase (Rs) — Resistance

.2 (default) | scalar

Stator phase resistance per phase, R_s , in ohm.

Stator d-axis inductance (Ldq_) – Inductance

3.752e-4 (default) | scalar

Stator inductance, L_{dq} , in H.**Permanent flux linkage constant (lambda_pm) – Flux**

0.1194 (default) | scalar

Permanent flux linkage constant, λ_{pm} , in Wb.**Back-emf constant (Ke) – Back electromotive force**

scalar

Back electromotive force, EMF, K_e , in peak Vpk_LL/krpm. Vpk_LL is the peak voltage line-to-line measurement.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{1}{\sqrt{3}} \cdot \frac{K_e}{1000P} \cdot \frac{60}{2\pi}$$

Torque constant (Kt) – Torque constant

scalar

Torque constant, K_t , in N·m/A.

To calculate the permanent flux linkage constant, the block implements this equation.

$$\lambda_{pm} = \frac{2}{3} \cdot \frac{K_t}{P}$$

Physical inertia, viscous damping, and static friction (mechanical) – Inertia, damping, friction

[0.002700, 4.924e-4, 0] (default) | vector

Mechanical properties of the motor:

- Inertia, J , in kg·m²
- Viscous damping, F , in N·m/(rad/s)
- Static friction, T_f , in N·m

Dependencies

To enable this parameter, select the Torque configuration parameter.

Initial Values**Initial d-axis and q-axis current (idq0) – Current**

[0 0] (default) | vector

Initial q- and d-axis currents, i_q , i_d , in A.**Initial mechanical position (theta_init) – Angle**

0 (default) | scalar

Initial motor angular position, θ_{m0} , in rad.

Initial mechanical speed (omega_init) – Speed

0 (default) | scalar

Initial angular velocity of the motor, ω_{m0} , in rad/s.

Dependencies

To enable this parameter, select the Torque configuration parameter.

Version History

Introduced in R2017a

References

- [1] Kundur, P. *Power System Stability and Control*. New York, NY: McGraw Hill, 1993.
- [2] Anderson, P. M. *Analysis of Faulted Power Systems*. Hoboken, NJ: Wiley-IEEE Press, 1995.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Surface Mount PM Controller | Flux-Based PMSM | Induction Motor | Interior PMSM | Mapped Motor

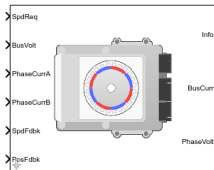
Topics

“Estimate Motor Parameters Using Motor Control Blockset Parameter Estimation Tool” (Motor Control Blockset)

Surface Mount PM Controller

Torque-based, field-oriented controller for a surface mount permanent magnet synchronous motor

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters
Motor Control Blockset / Electrical Systems / Motors

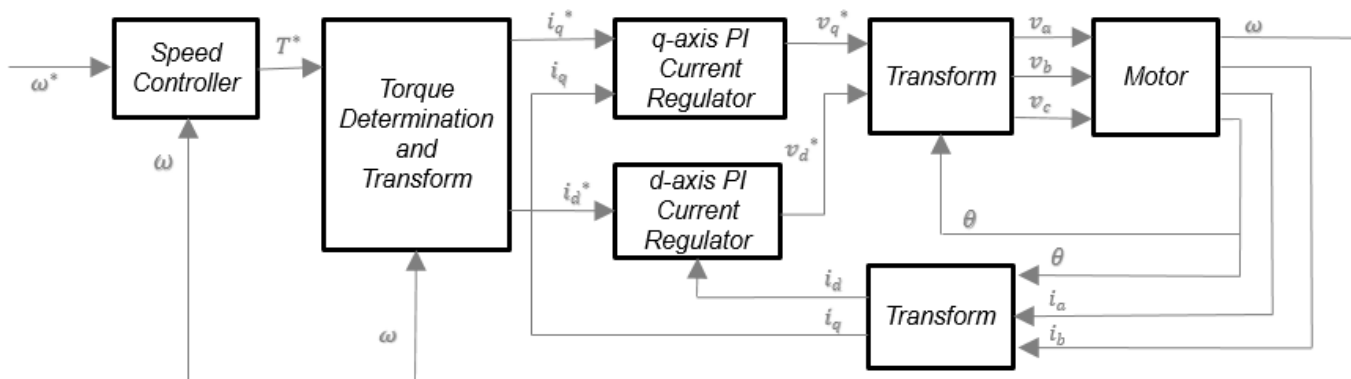


Description

The Surface Mount PM Controller block implements a torque-based, field-oriented controller for a surface mount permanent magnet synchronous motor (PMSM) with an optional outer-loop speed controller. The torque control utilizes quadrature current and does not weaken the magnetic flux. You can specify either speed or torque control.

The Surface Mount PM Controller implements equations for speed control, torque determination, regulators, transforms, and motors.

The figure illustrates the information flow in the block.



The block implements equations that use these variables.

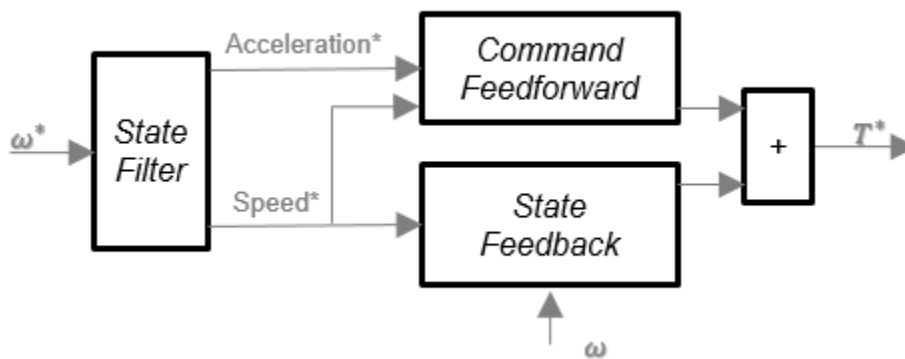
ω	Rotor speed
ω^*	Rotor speed command
T^*	Torque command
i_d	d-axis current
i_d^*	d-axis current command
i_q	q-axis current
i_q^*	q-axis current command

v_d	d-axis voltage
v_d^*	d-axis voltage command
v_q	q-axis voltage
v_q^*	q-axis voltage command
v_a, v_b, v_c	Stator phase a, b, c voltages
i_a, i_b, i_c	Stator phase a, b, c currents

Speed Controller

To implement the speed controller, select the **Control Type** parameter `Speed Control`. If you select the **Control Type** parameter `Torque Control`, the block does not implement the speed controller.

The speed controller determines the torque command by implementing a state filter, and calculating the feedforward and feedback commands. If you do not implement the speed controller, input a torque command to the Surface Mount PM Controller block.



State Filter

The state filter is a low-pass filter that generates the acceleration command based on the speed command. On the **Speed Controller** tab:

- To make the speed-command lag time negligible, specify a **Bandwidth of the state filter** parameter.
- To calculate a **Speed regulation time constant, Ksf** gain based on the state filter bandwidth, select **Calculate Speed Regulator Gains**.

The discrete form of characteristic equation is given by:

$$z + K_{sf}T_{sm} - 1$$

The filter calculates the gain using this equation.

$$K_{sf} = \frac{1 - \exp(-T_{sm}2\pi EV_{sf})}{T_{sm}}$$

The equations use these variables.

EV_{sf}	Bandwidth of the speed command filter
T_{sm}	Motion controller sample time
K_{sf}	Speed regulator time constant

State Feedback

To generate the state feedback torque, the block uses the filtered speed error signal from the state filter. The feedback torque calculation also requires gains for speed regulator.

On the **Speed Controller** tab, select **Calculate Speed Regulator Gains** to calculate:

- **Proportional gain, b_a**
- **Angular gain, K_{sa}**
- **Rotational gain, K_{isa}**

For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value on the **Motor Parameters** tab.

The gains for the state feedback are calculated using these equations.

Calculation	Equations
Discrete forms of characteristic equation	$z^3 + \frac{(-3J_p + T_s b_a + T_s^2 K_{sa} + T_s^3 K_{isa})}{J_p} z^2 + \frac{(3J_p - 2T_s b_a - T_s^2 K_{sa})}{J_p} z + \frac{-J_p + T_s b_a}{J_p}$ $(z - p_1)(z - p_2)(z - p_3) = z^3 + (p_1 + p_2 + p_3)z^2 + (p_1 p_2 + p_2 p_3 + p_1 p_3)z^2 - p_1 p_2 p_3$
Speed regulator proportional gain	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$
Speed regulator integral gain	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$
Speed regulator double integral gain	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
J_p	Motor inertia
T_{sm}	Motion controller sample time

Command Feedforward

To generate the state feedforward torque, the block uses the filtered speed and acceleration from the state filter. Also, the feedforward torque calculation uses the inertia, viscous damping, and static friction. To achieve zero tracking error, the torque command is the sum of the feedforward and feedback torque commands.

Selecting **Calculate Speed Regulator Gains** on the **Speed Controller** tab updates the inertia, viscous damping, and static friction with the **Physical inertia, viscous damping, static friction** parameter values on the **Motor Parameters** tab.

The feedforward torque command uses this equation.

$$T_{cmd_ff} = J_p \dot{\omega}_m + F_v \omega_m + F_s \frac{\omega_m}{|\omega_m|}$$

The equation uses these variables.

J_p	Motor inertia
T_{cmd_ff}	Torque command feedforward
F_s	Static friction torque constant
F_v	Viscous friction torque constant
F_s	Static friction torque constant
ω_m	Rotor speed

Torque Determination

The block uses a quadrature current to determine the base speed and the current commands. The available bus voltage determines the base speed. The direct (d) and quadrature (q) permanent magnet (PM) determines the induced voltage.

Calculation	Equations
Motor maximum torque	$T_{max} = \frac{3}{2}P(\lambda_{pm}i_q + (L_d - L_q)i_d i_q)$
Maximum q-axis phase current	$i_{q_max} = \frac{T_{cmd}}{\frac{3}{2}P\lambda_{pm}}$
Electrical base speed	$\omega_{base} = \frac{v_{max}}{\sqrt{(L_q i_q)^2 + (\lambda_{pm})^2}}$
d-axis voltage	$v_d = -\omega_e L_q i_{q_max}$
q-axis voltage	$v_q = \omega_e \lambda_{pm}$
Maximum phase current	$i_{max} = i_{q_max} $
Maximum voltage	$v_{max} = \frac{v_{bus}}{\sqrt{3}}$

Calculation	Equations
Current command	$i_{dref} = 0$ $i_{q_tmp} = \min(i_{q_max}, \frac{T_{cmd}}{\frac{3}{2}P\lambda_{pm}})$ <p>If $\omega_e \leq \omega_{base}$ $i_{qref} = i_{q_tmp}$</p> <p>Else</p> $i_{qfw} = \text{sqr}t(\min(0, \frac{1}{L_q}((\frac{v_{max}}{\omega_e})^2 - (\lambda_{pm})^2)))$ <p>If $i_{q_tmp} < i_{qfw}$ $i_{qref} = i_{q_tmp}$</p> <p>Else $i_{qref} = i_{qfw}$</p> <p>End</p> <p>End</p>

The equations use these variables.

i_{max}	Maximum phase current
i_d	d-axis current
i_q	q-axis current
i_{dref}	d-axis reference current
i_{qref}	q-axis reference current
i_{q_max}	Maximum q-axis phase current
ω_e	Rotor electrical speed
λ_{pm}	Permanent magnet flux linkage
v_d	d-axis voltage
v_q	q-axis voltage
v_{max}	Maximum line to neutral voltage
v_{bus}	DC bus voltage
L_d	d-axis winding inductance
L_q	q-axis winding inductance
P	Motor pole pairs
T_{max}	Motor maximum torque
T_{cmd}	Commanded motor maximum torque

Current Regulators

The block regulates the current with an anti-windup feature. Classic proportional-integrator (PI) current regulators do not consider the d-axis and q-axis coupling or the back-electromagnetic force (EMF) coupling. As a result, transient performance deteriorates. To account for the coupling, the block implements the complex vector current regulator (CVCR) in the scalar format of the rotor reference frame. The CVCR decouples:

- d-axis and q-axis current cross-coupling

- back-EMF cross-coupling

The current frequency response is a first-order system, with a bandwidth of $EV_{current}$.

The block implements these equations.

Calculation	Equations
Motor voltage, in the rotor reference frame	$L_d \frac{di_d}{dt} = v_d - R_s i_d + p \omega_m L_q i_q$ $L_q \frac{di_q}{dt} = v_q - R_s i_q - p \omega_m L_d i_d - p \omega_m \lambda_{pm}$
Current regulator gains	$\omega_b = 2\pi EV_{current}$ $K_{p_d} = L_d \omega_b$ $K_{p_q} = L_q \omega_b$ $K_i = R_s \omega_b$
Transfer functions	$\frac{i_d}{i_{dref}} = \frac{\omega_b}{s + \omega_b}$ $\frac{i_q}{i_{qref}} = \frac{\omega_b}{s + \omega_b}$

The equations use these variables.

$EV_{current}$	Current regulator bandwidth
i_d	d-axis current
i_q	q-axis current
K_{p_d}	Current regulator d-axis gain
K_{p_q}	Current regulator q-axis gain
K_i	Current regulator integrator gain
L_d	d-axis winding inductance
L_q	q-axis winding inductance
R_s	Stator phase winding resistance
ω_m	Rotor speed
v_d	d-axis voltage
v_q	q-axis voltage
λ_{pm}	Permanent magnet flux linkage
P	Motor pole pairs

Transforms

To calculate the voltages and currents in balanced three-phase (a, b) quantities, quadrature two-phase (α, β) quantities, and rotating (d, q) reference frames, the block uses the Clarke and Park Transforms.

In the transform equations.

$$\omega_e = P\omega_m$$

$$\frac{d\theta_e}{dt} = \omega_e$$

Transform	Description	Equations
Clarke	Converts balanced three-phase quantities (a, b) into balanced two-phase quadrature quantities (α, β).	$x_\alpha = \frac{2}{3}x_a - \frac{1}{3}x_b - \frac{1}{3}x_c$ $x_\beta = \frac{\sqrt{3}}{2}x_b - \frac{\sqrt{3}}{2}x_c$
Park	Converts balanced two-phase orthogonal stationary quantities (α, β) into an orthogonal rotating reference frame (d, q).	$x_d = x_\alpha \cos\theta_e + x_\beta \sin\theta_e$ $x_q = -x_\alpha \sin\theta_e + x_\beta \cos\theta_e$
Inverse Clarke	Converts balanced two-phase quadrature quantities (α, β) into balanced three-phase quantities (a, b).	$x_a = x_\alpha$ $x_b = -\frac{1}{2}x_\alpha + \frac{\sqrt{3}}{2}x_\beta$ $x_c = -\frac{1}{2}x_\alpha - \frac{\sqrt{3}}{2}x_\beta$
Inverse Park	Converts an orthogonal rotating reference frame (d, q) into balanced two-phase orthogonal stationary quantities (α, β).	$x_\alpha = x_d \cos\theta_e - x_q \sin\theta_e$ $x_\beta = x_d \sin\theta_e + x_q \cos\theta_e$

The transforms use these variables.

ω_m	Rotor speed
P	Motor pole pairs
ω_e	Rotor electrical speed
θ_e	Rotor electrical angle
x	Phase current or voltage

Motor

The block uses the phase currents and phase voltages to estimate the DC bus current. Positive current indicates battery discharge. Negative current indicates battery charge. The block uses these equations.

Load power	$Ld_{Pwr} = v_a i_a + v_b i_b + v_c i_c$
Source power	$Src_{Pwr} = Ld_{Pwr} + Pwr_{Loss}$
DC bus current	$i_{bus} = \frac{Src_{Pwr}}{v_{bus}}$
Estimated rotor torque	$MtrTrq_{est} = 1.5P[\lambda i_q + (L_d - L_q)i_d i_q]$
Power loss for single efficiency source to load	$Pwr_{Loss} = \frac{100 - Eff}{Eff} \cdot Ld_{Pwr}$
Power loss for single efficiency load to source	$Pwr_{Loss} = \frac{100 - Eff}{100} \cdot Ld_{Pwr} $

Power loss for tabulated efficiency	$Pwr_{Loss} = f(\omega_m, MtrTrq_{est})$
-------------------------------------	--

The equations use these variables.

v_a, v_b, v_c	Stator phase a, b, c voltages
v_{bus}	Estimated DC bus voltage
i_a, i_b, i_c	Stator phase a, b, c currents
i_{bus}	Estimated DC bus current
Eff	Overall inverter efficiency
ω_m	Rotor mechanical speed
L_q	q-axis winding inductance
L_d	d-axis winding inductance
i_q	q-axis current
i_d	d-axis current
λ	Permanent magnet flux linkage
P	Motor pole pairs

Electrical Losses

To specify the electrical losses, on the **Electrical Losses** tab, for **Parameterize losses by**, select one of these options.

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use **Tabulated loss data** instead of **Tabulated efficiency data**:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Ports

Input

SpdReq — Rotor speed command

scalar

Rotor speed command, ω_m^* , in rad/s.

Dependencies

To create this port, select Speed Control for the **Control Type** parameter.

TrqCmd — Torque command

scalar

Torque command, T^* , in N·m.

Dependencies

To create this port, select Torque Control for the **Control Type** parameter.

BusVlt — DC bus voltage

scalar

DC bus voltage v_{bus} , in V.

PhaseCurrA — Current

scalar

Stator current phase a, i_a , in A.

PhaseCurrB — Current

scalar

Stator current phase b, i_b , in A.

SpdFdbk — Rotor speed

scalar

Rotor speed, ω_m , in rad/s.

PosFdbk — Rotor electrical angle

scalar

Rotor electrical angle, θ_m , in rad.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Units
SrcPwr	Source power	W
LdPwr	Load power	W
PwrLoss	Power loss	W
MtrTrqEst	Estimated motor torque	N·m

BusCurr – Bus current

scalar

Estimated DC bus current, i_{bus} , in A.

PhaseVolt – Stator terminal voltages

array

Stator terminal voltages, V_a , V_b , and V_c , in V.

Parameters

Configuration

Control Type – Select control

Speed Control (default) | Torque Control

If you select Torque Control, the block does not implement the speed controller.

This table summarizes the port configurations.

Port Configuration	Creates Ports
Speed Control	SpdReq
Torque Control	TrqCmd

Motor Parameters

Stator resistance, Rs – Resistance

0.02 (default) | scalar

Stator phase winding resistance, R_s , in ohm.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Stator resistance, Rs	D and Q axis integral gain, Ki	Current Controller

DQ axis inductance, Ldq – Inductance

1.7e-3 (default) | scalar

D-axis winding inductance, L_{dq} , in H.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
DQ axis inductance, Ldq	D-axis proportional gain, Kp_d Q-axis proportional gain, Kp_q D and Q axis integral gain, Ki	Current Controller

Permanent magnet flux, lambda_pm – Flux

0.2205 (default) | scalar

Permanent magnet flux, λ_{pm} , in Wb.

Number of pole pairs, PolePairs – Poles

4 (default) | scalar

Motor pole pairs, P .

Physical inertia, viscous damping, static friction, Mechanical – Inertia, damping, friction

[0.0027, 4.924e-4, 0] (default) | vector

Mechanical properties of the motor:

- Motor inertia, F_v , in kgm^2
- Viscous friction torque constant, F_v , in $\text{N}\cdot\text{m}/(\text{rad}/\text{s})$
- Static friction torque constant, F_s , in $\text{N}\cdot\text{m}$

Dependencies

To enable this parameter, set the **Control Type** parameter to Speed Control.

For the gain calculations, the block uses the inertia from the **Physical inertia, viscous damping, static friction** parameter value that is on the **Motor Parameters** tab.

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Physical inertia, viscous damping, static friction, Mechanical	Proportional gain, ba Angular gain, Ksa Rotational gain, Kisa Inertia compensation, Jcomp Viscous damping compensation, Fv Static friction, Fs	Speed Controller

Id and Iq Calculation

Maximum torque, T_max – Torque

60 (default) | scalar

Maximum torque, in N·m.

Current Controller

Bandwidth of the current regulator, EV_current – Bandwidth

200 (default) | scalar

Current regulator bandwidth, in Hz.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the current regulator, EV_current	D-axis proportional gain, Kp_d Q-axis proportional gain, Kp_q D and q axis proportional gain, Ki	Current Controller

Sample time for the torque control, Tst – Time

5e-5 (default) | scalar

Torque control sample time, in s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Used to Derive	
	Parameter	Tab
Sample time for the torque control, Tst	Speed regulation time constant, Ksf	Speed Controller

Calculate Current Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Current Controller** tab, when you select **Calculate Current Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Current Controller tab	Dependency	
	Parameter	Tab
D-axis proportional gain, Kp_d	Bandwidth of the current regulator, EV_current	Current Controller
Q-axis proportional gain, Kp_q	Stator resistance, Rs	Motor Parameters
D and Q axis integral gain, Ki	DQ-axis inductance, Ldq	

D-axis proportional gain, Kp_d – Derived

0.47149 (default) | scalar

Derived d-axis proportional gain, in V/A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D-axis proportional gain, Kp_d	Bandwidth of the current regulator, EV_current	Current Controller
	DQ-axis inductance, Ldq	Motor Parameters

Q-axis proportional gain, Kp_q – Derived

0.52125 (default) | scalar

Derived q-axis proportional gain, in V/A.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Q-axis proportional gain, Kp_q	Bandwidth of the current regulator, EV_current	Current Controller
	DQ-axis inductance, Ldq	Motor Parameters

D and Q axis integral gain, Ki – Derived

251.3274 (default) | scalar

Derived axis integral gain, in V/A*s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
D and Q axis integral gain, Ki	Bandwidth of the current regulator, EV_current	Current Controller
	Stator resistance, Rs	Motor Parameters
	DQ-axis inductance, Ldq	

Speed Controller

Bandwidth of the motion controller, EV_motion – Bandwidth

[20, 4, 0.8] (default) | vector

Motion controller bandwidth, in Hz. Set the first element of the vector to the desired cutoff frequency. Set the second and third elements of the vector to the higher-order cut off frequencies. You can set the value of the next element to 1/5 the value of the previous element. For example, if the desired cutoff frequency is 20 Hz, specify [20 4 0.8].

Dependencies

The parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the motion controller, EV_motion	Proportional gain, ba	Speed Controller
	Angular gain, Ksa	
	Rotational gain, Kisa	

Bandwidth of the state filter, EV_sf – Bandwidth

200 (default) | scalar

State filter bandwidth, in Hz.

Dependencies

The parameter is enabled when the **Control Type** parameter is set to Speed Control.

Parameter	Used to Derive	
	Parameter	Tab
Bandwidth of the state filter, EV_sf	Speed regulation time constant, Ksf	Speed Controller

Calculate Speed Regulator Gains – Derive parameters

button

Click to derive parameters.

Dependencies

On the **Speed Controller** tab, when you select **Calculate Speed Regulator Gains**, the block calculates derived parameters. The table summarizes the derived parameters that depend on other block parameters.

Derived Parameter on Speed Controller tab		Depends On	
		Parameter	Tab
Proportional gain, ba	$b_a = \frac{J_p - J_p p_1 p_2 p_3}{T_{sm}}$	Bandwidth of the motion controller, EV_motion Bandwidth of the state filter, EV_sf	Speed Controller
Angular gain, Ksa	$K_{sa} = \frac{J_p(p_1 p_2 + p_2 p_3 + p_3 p_1) - 3J_p + 2b_a T_{sm}}{T_{sm}^2}$	Sample time for the torque control, Tst	Current Controller
Rotational gain, Kisa	$K_{isa} = \frac{-J_p(p_1 + p_2 + p_3) + 3J_p - b_a T_{sm} - K_{sa} T_{sm}^2}{T_{sm}^3}$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
Speed regulation time constant, Ksf	$K_{sf} = \frac{1 - \exp(-T_{sm} 2\pi EV_{sf})}{T_{sm}}$		
Inertia compensation, Jcomp	$J_{comp} = J_p$	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
Viscous damping compensation, Fv	F_v		
Static friction, Fs	F_s		

The equations use these variables.

P	Motor pole pairs
b_a	Speed regulator proportional gain
K_{sa}	Speed regulator integral gain
K_{isa}	Speed regulator double integral gain
K_{sf}	Speed regulator time constant
J_p	Motor inertia
EV_{sf}	State filter bandwidth
EV_{motion}	Motion controller bandwidth

Proportional gain, b_a – Derived

3.7477 (default) | scalar

Derived proportional gain, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Proportional gain, b_a	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_{motion}	Speed Controller

Angular gain, K_{sa} – Derived

94.0877 (default) | scalar

Derived angular gain, in N·m/rad.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Angular gain, K_{sa}	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_{motion}	Speed Controller

Rotational gain, K_{isa} – Derived

381.7822 (default) | scalar

Derived rotational gain, in N·m/(rad*s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Rotational gain, Kisa	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters
	Bandwidth of the motion controller, EV_motion	Speed Controller

Speed regulation time constant, Ksf – Derived

1217.9727 (default) | scalar

Derived speed regulation time constant, in 1/s.

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Speed regulation time constant, Ksf	Sample time for the torque control, Tst	Current Controller
	Bandwidth of the state filter, EV_sf	Speed Controller

Inertia compensation, Jcomp – Derived

0.025 (default) | scalar

Derived inertia compensation, in kg·m².**Dependencies**

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Inertia compensation, Jcomp	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Viscous damping compensation, Fv – Derived

0 (default) | scalar

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Viscous damping compensation, Fv	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Static friction, Fs – Derived

0 (default) | scalar

Derived static friction, in N·m/(rad/s).

Dependencies

This table summarizes the parameter dependencies.

Parameter	Dependency	
	Parameter	Tab
Static friction, Fs	Physical inertia, viscous damping, static friction, Mechanical	Motor Parameters

Electrical Losses

Parameterize losses by – Select type

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

Setting	Block Implementation
Single efficiency measurement	Electrical loss calculated using a constant value for inverter efficiency.
Tabulated loss data	Electrical loss calculated as a function of motor speeds and load torques.
Tabulated efficiency data	<p>Electrical loss calculated using inverter efficiency that is a function of motor speeds and load torques.</p> <ul style="list-style-type: none"> Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

For best practice, use Tabulated loss data instead of Tabulated efficiency data:

- Efficiency becomes ill defined for zero speed or zero torque.

- You can account for fixed losses that are still present for zero speed or torque.

Overall inverter efficiency, *eff* – Constant

98 (default) | scalar

Overall inverter efficiency, *Eff*, in %.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of speeds (*w*) for tabulated loss, *w_loss_bp* – Breakpoints

[0 200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating losses, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of torques (*T*) for tabulated loss, *T_loss_bp* – Breakpoints

[0 25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating losses, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Corresponding losses, *losses_table* – Table

[100 100 100 100 100;100 150 200 250 300;100 200 300 400 500;100 250 400 550 700;100 300 500 700 900;100 350 600 850 1100] (default) | M-by-N array

Array of values for electrical losses as a function of M speeds and N torques, in W. Each value specifies the losses for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated loss data.

Vector of speeds (*w*) for tabulated efficiency, *w_eff_bp* – Breakpoints

[200 400 600 800 1000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating efficiency, in rad/s.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Vector of torques (*T*) for tabulated efficiency, *T_eff_bp* – Breakpoints

[25 50 75 100] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating efficiency, in N·m.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Corresponding efficiency, efficiency_table – Table

[96.2 98.1 98.7 99;98.1 99 99.4 99.5;98.7 99.4 99.6 99.7;99 99.5 99.7 99.8;99.2 99.6 99.7 99.8] (default) | M-by-N array

Array of efficiency as a function of M speeds and N torque, in %. Each value specifies the efficiency for a specific combination of speed and torque. The matrix size must match the dimensions defined by the speed and torque vectors.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To enable this parameter, for **Parameterize losses by**, select Tabulated efficiency data.

Version History

Introduced in R2017a

References

- [1] Lorenz, Robert D., Thomas Lipo, and Donald W. Novotny. "Motion control with induction motors." *Proceedings of the IEEE*, Vol. 82, Issue 8, August 1994, pp. 1215-1240.
- [2] Shigeo Morimoto, Masayuka Sanada, Yoji Takeda. "Wide-speed operation of interior permanent magnet synchronous motors with high-performance current regulator." *IEEE Transactions on Industry Applications*, Vol. 30, Issue 4, July/August 1994, pp. 920-926.
- [3] Muyang Li. "Flux-Weakening Control for Permanent-Magnet Synchronous Motors Based on Z-Source Inverters." Master's Thesis, Marquette University, e-Publications@Marquette, Fall 2014.
- [4] Briz, Fernando, Michael W. Degner, and Robert D. Lorenz. "Analysis and design of current regulators using complex vectors." *IEEE Transactions on Industry Applications*, Vol. 36, Issue 3, May/June 2000, pp. 817-825.
- [5] Briz, Fernando, et al. "Current and flux regulation in field-weakening operation [of induction motors]." *IEEE Transactions on Industry Applications*, Vol. 37, Issue 1, Jan/Feb 2001, pp. 42-50.

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

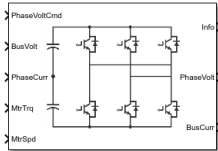
See Also

Surface Mount PMSM | Flux-Based PM Controller | IM Controller | Interior PM Controller

Three-Phase Voltage Source Inverter

Three-phase voltage source inverter

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters



Description

The Three-Phase Voltage Source Inverter block implements a three-phase voltage source inverter that generates neutral voltage commands for a balanced three-phase load. Configure the voltage switching function for continuous vector modulation or inverter switch input signals. You can incorporate the block into a closed-loop model to simulate a power inverter. The block controls the ideal switch states.

To enable power loss calculations suitable for code generation targets that limit memory, select **Enable memory optimized 2D LUT**. Click **Calibrate Maps** to virtually calibrate an inverter power loss lookup table as a function of motor torque and motor speed.

If you select **Input inverter temperature**, click **Calibrate Maps** to virtually calibrate the power loss table as a function of motor torque, motor speed, and inverter temperature. You cannot enable memory optimization for the 3D power loss lookup table.

Use the **Switching voltage function** parameter to set the switching voltage function.

Setting	Implementation	Illustration
Commanded phase voltage	Phase a, b, c line-to-neutral voltage command input. Suitable for continuous sinusoidal or space vector modulation input signals.	

Setting	Implementation	Illustration
Switch inputs (default)	Inverter switch input command. Suitable for hardware-in-the-loop (HIL) simulation. The inverter switches S1, S3, and S5 using complimented control for S2, S4, and S6.	

Virtual Calibration

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the lookup tables using measured data. The dialog box steps through these tasks.

Task	Description						
Import Loss Data	Import this loss data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autoblksshared/mbctemplates/MappedInverterDataset.xlsx</code> . For more information, see “Using Data” (Model-Based Calibration Toolbox).						
	<table border="1"> <thead> <tr> <th>Input inverter temperature Setting</th> <th>Required Data</th> </tr> </thead> <tbody> <tr> <td>off</td> <td> <ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Power loss, W </td> </tr> <tr> <td>on</td> <td> <ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Motor temperature, K Power loss, W </td> </tr> </tbody> </table>	Input inverter temperature Setting	Required Data	off	<ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Power loss, W 	on	<ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Motor temperature, K Power loss, W
Input inverter temperature Setting	Required Data						
off	<ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Power loss, W 						
on	<ul style="list-style-type: none"> Motor speed, rad/s Motor torque, N·m Motor temperature, K Power loss, W 						
	Collect inverter data at steady-state operating conditions. Data should cover the inverter speed, torque, and temperature operating range. To filter or edit the data, select Edit in Application . The Model-Based Calibration Toolbox Data Editor opens.						

Task	Description						
Generate Response Models	<p>Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>						
Generate Calibration	<p>Model-Based Calibration Toolbox calibrates the response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>						
Update block parameters	<p>Update these parameters with the calibration.</p> <table border="1"> <thead> <tr> <th>Input inverter temperature Setting</th> <th>Parameters</th> </tr> </thead> <tbody> <tr> <td>off</td> <td> <ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding power loss, ploss_table </td> </tr> <tr> <td>on</td> <td> <ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, Temp_eff_bp • Corresponding power loss, ploss_table_3d </td> </tr> </tbody> </table>	Input inverter temperature Setting	Parameters	off	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding power loss, ploss_table 	on	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, Temp_eff_bp • Corresponding power loss, ploss_table_3d
Input inverter temperature Setting	Parameters						
off	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding power loss, ploss_table 						
on	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, Temp_eff_bp • Corresponding power loss, ploss_table_3d 						

Switching Function

For the switch voltage, the block implementation depends on the **Switching voltage function** setting.

Setting	Calculation	Equations
Commanded phase voltage	Continuous line-to-neutral voltage commands set to phase a, b, c line-to-neutral voltage command input	$v_{an} = v_{a_cmd}$ $v_{bn} = v_{b_cmd}$ $v_{cn} = v_{c_cmd}$
	Line-to-line voltage	$v_{ab} = v_{an} - v_{bn}$ $v_{bc} = v_{bn} - v_{cn}$ $v_{ca} = v_{cn} - v_{an}$

Setting	Calculation	Equations
Switch inputs	Switching function	$SF_a = \begin{cases} 1 & \text{S1 on and S2 off} \\ -1 & \text{S1 off and S2 on} \end{cases}$ $SF_b = \begin{cases} 1 & \text{S3 on and S4 off} \\ -1 & \text{S3 off and S4 on} \end{cases}$ $SF_c = \begin{cases} 1 & \text{S5 on and S6 off} \\ -1 & \text{S5 off and S6 on} \end{cases}$
	Line-to-center point voltage	$v_{ao} = \frac{v_{bus}}{2} SF_a$ $v_{bo} = \frac{v_{bus}}{2} SF_b$ $v_{co} = \frac{v_{bus}}{2} SF_c$
	Line-to-neutral voltage	$v_{an} = v_{ao} - v_{no}$ $v_{bn} = v_{bo} - v_{no}$ $v_{cn} = v_{co} - v_{no}$ $v_{an} + v_{bn} + v_{cn} = 0$ $v_{no} = \frac{1}{3}(v_{ao} + v_{bo} + v_{co})$ $v_{an} = v_{ao} - \frac{1}{3}(v_{ao} + v_{bo} + v_{co})$ $v_{bn} = v_{bo} - \frac{1}{3}(v_{ao} + v_{bo} + v_{co})$ $v_{cn} = v_{co} - \frac{1}{3}(v_{ao} + v_{bo} + v_{co})$
	Line-to-line voltage	$v_{ab} = v_{an} - v_{bn}$ $v_{bc} = v_{bn} - v_{cn}$ $v_{ca} = v_{cn} - v_{an}$

The equations use these variables.

SF_a, SF_b, SF_c	Phase a, b, c line switching functions, respectively
v_{bus}	Power source bus voltage
V_{ao}, V_{bo}, V_{co}	Phase a, b, c line-to-center voltage, respectively
V_{an}, V_{bn}, V_{cn}	Phase a, b, c line-to-neutral voltage, respectively
V_{ab}, V_{bc}, V_{ca}	Phase ab, bc, ca line-to-neutral voltage, respectively
$V_{a_cmd}, V_{b_cmd}, V_{c_cmd}$	Phase a, b, c line-to-neutral voltage commands, respectively

Current and Power Loss

For the line-to-center, line-to-neutral, and line-to-line voltage, the block implements these equations.

Calculation	Equations
Motor and bus power	$P_{mtr} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c$ $P_{bus} = v_{bus}i_{bus}$
Inverter power loss and bus current	$P_{in} = P_{bus} = v_{bus}i_{bus}$ $P_{out} = P_{mtr} = v_{an}i_a + v_{bn}i_b + v_{cn}i_c + P_{LossInv}$ $i_{bus} = \frac{v_{an}i_a + v_{bn}i_b + v_{cn}i_c + P_{LossInv}}{v_{bus}}$

The equations use these variables.

P_{mtr}	Power delivered to the motor
P_{bus}	Power from input bus
P_{loss}	Power loss
i_{bus}	Power source bus current
i_a, i_b, i_c	Phase a, b, c line current, respectively
V_{an}, V_{bn}, V_{cn}	Phase a, b, c line-to-neutral voltage, respectively
v_{bus}	Power source bus voltage

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equation
PwrIn fo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrMtr	Power delivered to the motor	$P_{TrnsfrdMtr} = -(v_{an}i_a + v_{bn}i_b + v_{cn}i_c)$
		PwrBus	Power from input bus	$P_{TrnsfrdBus} = P_{bus}$

Bus Signal		Description	Variable	Equation
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrLoss	Power loss Negative value indicates power loss	$P_{NotTrnsfrd}$	$P_{NotTrnsfrd} = - (P_{TrnsfrdBus} + P_{TrnsfrdMtr})$
PwrStored — Stored energy rate of change		<i>Not used</i>		
<ul style="list-style-type: none"> • Positive signals indicate an input • Negative signals indicate a loss 				
<ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 				

Lookup Table Memory Optimization

The inverter power loss table parameter **Corresponding power loss, ploss_table** data is a function of motor torque and motor speed at different battery voltages. Positive current indicates battery discharge. Negative current indicates battery charge.

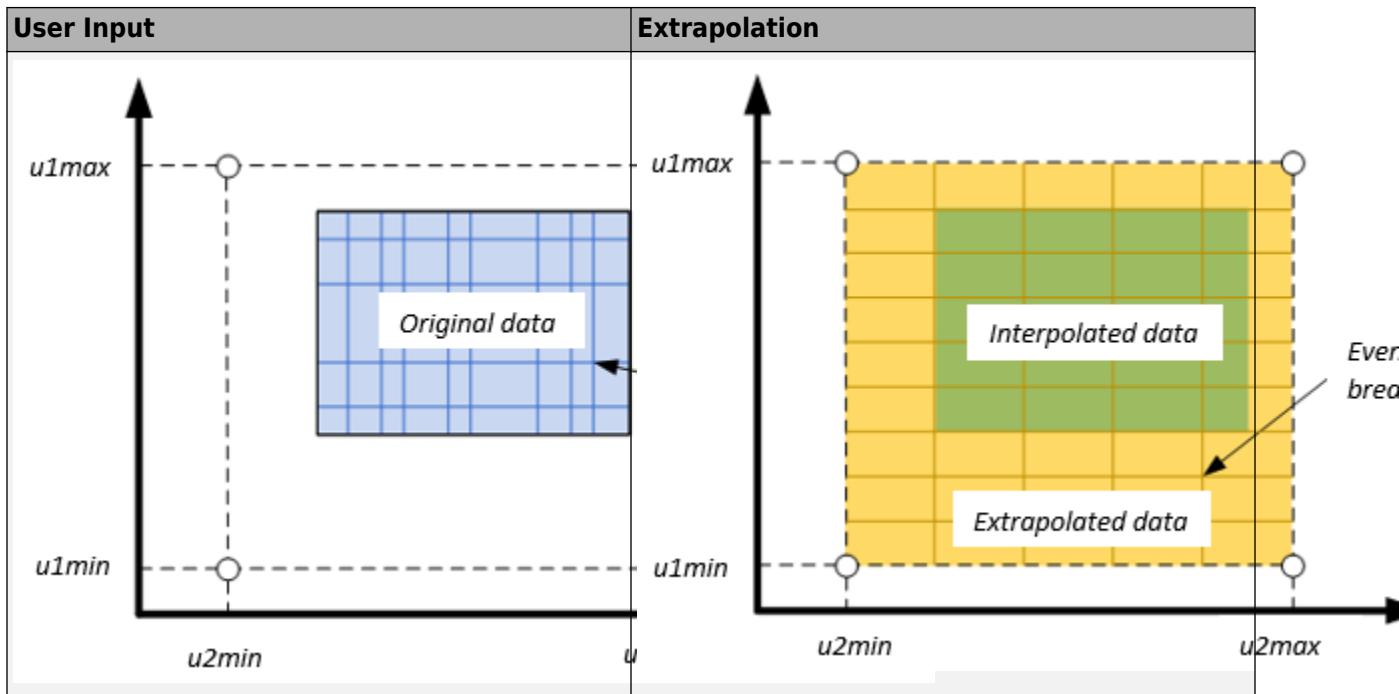
To enable power loss calculations suitable for code generation targets that limit memory, select **Enable memory optimized 2D LUT**. The block uses linear interpolation to optimize the inverter power loss lookup table values for code generation. This table summarizes the optimization implementation.

Use Case	Implementation
Motor speed and torque input align with the lookup table breakpoint values.	Memory-optimized power loss is power loss lookup table value at intersection of motor speed and torque.
Motor speed and torque input do not align with the lookup table breakpoint values, but are within range.	Memory-optimized power loss is linear interpolation between corresponding motor speed and torque.
Motor speed and torque input do not align with the lookup table breakpoint values, and are out of range.	Cannot compute a memory-optimized power loss. Block uses extrapolated data.

Extrapolation

The lookup tables optimized for code generation do not support extrapolation for data that is out of range. However, you can include pre-calculated extrapolation values in the power loss lookup table by selecting **Specify Extrapolation**.

The block uses the endpoint parameters to resize the table data.



Ports

Input

PhaseVoltCmd — Phase a, b, c line-to-neutral voltage command

1-by-3 array

Phase a, b, c line-to-neutral voltage command, V_{a_cmd} , V_{b_cmd} , and V_{c_cmd} , in V.

Dependencies

To create this port, set **Switching voltage function** to Commanded phase voltage.

SwitchCmd — Switch commands

1-by-3 array

Switch commands, S_a , S_b , and S_c , dimensionless.

Dependencies

To create this port, set **Switching voltage function** to Switch inputs.

BusVolt — Power source bus voltage

bus

Power source bus voltage, V_{bus} , in V.

PhaseCurr — Phase a, b, c current

1-by-3 array

Phase a, b, c current, i_a , i_b , and i_c , in A.

MtrTrq — Motor torque

scalar

Motor torque, T_{mtr} , in N·m.

MtrSpd — Motor speed

scalar

Angular speed of the motor, ω_{mtr} , in rad/s.

InvrtrTemp — Inverter operating temperature

scalar

Inverter operating temperature, $Temp_{Invtrtr}$, in K.

Dependencies

To create this port, select **Input inverter temperature**.

Output

Info — Bus signal

bus

The bus signal contains these block calculations.

Signal			Description	Variable	Units
BusCurr			Power source bus current	i_{bus}	A
PwrLossInv			Inverter power loss	ϵ_{inv}	dimensionless
PwrInfo	PwrTrnsfrd	PwrMtr	Power delivered to the motor	$P_{TrnsfrdMtr}$	W
		PwrBus	Power from input bus	$P_{TrnsfrdBus}$	W
	PwrNotTrnsfrd	PwrLoss	Power loss	$P_{NotTrnsfrd}$	W
	PwrStored		Not used		

PhaseVlt — Phase a, b, c line-to-neutral voltage

1-by-3 array

Phase a, b, c line-to-neutral voltage, V_{an} , V_{bn} , and V_{cn} , in V.

BusCurr — Power source bus current

scalar

Power source bus current, i_{bus} , in A.

Parameters

Block Options

Input inverter temperature — Create input port

off (default) | on

Select this parameter to create the `InvrtrTemp` input port.

The block enables you to specify inverter power loss lookup tables that are functions of motor torque, T_{mtr} , and motor speed, ω_{mtr} . If you select **Input inverter temperature**, the tables are also a function of the inverter temperature, $Temp_{Invrtr}$.

Input Inverter Temperature Parameter Setting	Enables Efficiency Table	Function Of
off	Corresponding power loss, <code>ploss_table</code>	$f(T_{mtr}, \omega_{mtr})$
on	Corresponding power loss, <code>ploss_table_3d</code>	$f(T_{mtr}, \omega_{mtr}, Temp_{Invrtr})$

Dependencies

If you select **Input inverter temperature** to specify a 3D power loss lookup table as a function of motor torque, motor speed, and inverter temperature, you cannot select **Enable memory optimized 2D LUT** to enable a memory optimization.

Enable memory optimized 2D LUT – Selection

off (default) | on

Enable generation of memory-optimized lookup tables, suitable code generation targets that limit memory.

Dependencies

If you select **Enable memory optimized 2D LUT**, you cannot select **Input inverter temperature**.

Calibrate Maps – Calibrate tables with measured data

selection

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the lookup tables using measured data. The dialog box steps through these tasks.

Task	Description						
Import Loss Data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autoblksshared/mbctemplates/MappedInverterDataset.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <table border="1" data-bbox="505 478 1469 886"> <thead> <tr> <th data-bbox="505 478 756 583">Input inverter temperature Setting</th> <th data-bbox="756 478 1469 583">Required Data</th> </tr> </thead> <tbody> <tr> <td data-bbox="505 583 756 716">off</td> <td data-bbox="756 583 1469 716"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W </td> </tr> <tr> <td data-bbox="505 716 756 886">on</td> <td data-bbox="756 716 1469 886"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W </td> </tr> </tbody> </table> <p>Collect inverter data at steady-state operating conditions. Data should cover the inverter speed, torque, and temperature operating range.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Input inverter temperature Setting	Required Data	off	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 	on	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W
Input inverter temperature Setting	Required Data						
off	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 						
on	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W 						
Generate Response Models	<p>Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>						
Generate Calibration	<p>Model-Based Calibration Toolbox calibrates the response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>						

Task	Description	
Update block parameters	Update these parameters with the calibration.	
	Input inverter temperature Setting	Parameters
	off	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding power loss, $ploss_table$
on	<ul style="list-style-type: none"> • Vector of speeds (w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, $Temp_eff_bp$ • Corresponding power loss, $ploss_table_3d$ 	

Electrical Model

Switching voltage function – Selection

Commanded phase voltage (default) | Switch inputs

Use the **Switching voltage function** parameter to set the switching voltage function.

Setting	Implementation	Illustration
Commanded phase voltage	Phase a, b, c line-to-neutral voltage command input. Suitable for continuous sinusoidal or space vector modulation input signals.	

Setting	Implementation	Illustration
Switch inputs (default)	Inverter switch input command. Suitable for hardware-in-the-loop (HIL) simulation. The inverter switches S1, S3, and S5 using complimented control for S2, S4, and S6.	

Vector of speeds (w) for tabulated losses, w_eff_bp – Speed breakpoints
 [-1000 -500 0 500 1000] (default) | 1-by-M vector

Vector of motor speed, ω_{mtr} , breakpoints for power loss, in rad/s. If you set **Enable memory optimized 2D LUT**, the block converts the data to single precision.

Resample storage size for w_eff_bp , $n1$ – Speed bit size
 128 (default) | 2 | 4 | 8 | 16 | 32 | 64 | 256

Speed breakpoint storage size, $n1$, dimensionless. The block resamples the **Corresponding power loss, $ploss_table$** data based on the storage size.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT**.

Vector of torques (T) for tabulated losses, T_eff_bp – Torque breakpoints
 [-200 -100 0 100 200] (default) | 1-by-N vector

Vector of motor torque, T_{mtr} , breakpoints for power loss, in N·m. If you set **Enable memory optimized 2D LUT**, the block converts the data to single precision.

Resample storage size for T_eff_bp , $n2$ – Torque bit size
 128 (default) | 2 | 4 | 8 | 16 | 32 | 64 | 256

Torque breakpoint storage size, $n2$, dimensionless. The block resamples the **Corresponding power loss, $ploss_table$** data based on the storage size.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT**.

Vector of temperatures for tabulated losses, $Temp_eff_bp$ – Temperature breakpoints
 [213.15 293.15 373.15] (default) | 1-by-L vector

Vector of inverter temperature, $Temp_{Invtr}$, breakpoints for power loss, in K.

Dependencies

To create this parameter, select **Input inverter temperature**.

Corresponding power loss, ploss_table — 2D lookup table

[1 0.999 0.989 0.997 0.996;0.995 0.994 0.993 0.992 0.991;0.990 0.989 0.988
0.987 0.986;0.985 0.984 0.983 0.982 0.981;0.980 0.979 0.978 0.977 0.976]
(default) | M-by-N array

Array of values for power loss as a function of M motor speeds, ω_{mtr} , and N motor torques, T_{mtr} , in W. Each value specifies the power loss for a specific combination of motor speed and motor torque. The array size must match the dimensions defined by the speed and torque vectors.

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the lookup table using measured data.

If you set **Enable memory optimized 2D LUT**, the block converts the data to single precision.

Dependencies

To create this parameter, clear **Input inverter temperature**.

Corresponding power loss, ploss_table_3d — 3D lookup table

M-by-N-by-L array

Array of values for power loss as a function of M motor speeds, ω_{mtr} , N motor torques, T_{mtr} , and L motor temperatures, $Temp_{Invtr}$, in W. Each value specifies the power loss for a specific combination of motor speed, motor torque, and temperature. The array size must match the dimensions defined by the speed, torque, and temperature vectors.

If you have Model-Based Calibration Toolbox, click **Calibrate Maps** to virtually calibrate the lookup table using measured data.

Dependencies

To create this parameter, select **Input inverter temperature**.

Specify Extraction**w_eff_bp max endpoint, u1max — Speed breakpoint**

1000 (default) | scalar

Speed breakpoint maximum extrapolation endpoint, $u1max$, in rad/s.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

w_eff_bp min endpoint, u1min — Speed breakpoint

-1000 (default) | scalar

Speed breakpoint minimum extrapolation endpoint, $u1min$, in rad/s.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

T_eff_bp max endpoint, u2max – Torque breakpoint

200 (default) | scalar

Torque breakpoint maximum extrapolation endpoint, $u2max$, in rad/s.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

T_eff_bp min endpoint, u2min – Torque breakpoint

-200 (default) | scalar

Torque breakpoint minimum extrapolation endpoint, $u2min$, in rad/s.

Dependencies

To create this parameter, select **Enable memory optimized 2D LUT** and **Specify Extrapolation**.

Version History

Introduced in R2019a

References

- [1] Lee, Byoung-Kuk and Mehrdad Ehsami. "A simplified functional simulation model for three-phase voltage-source inverter using switching function concept." *IEEE Transactions on Industrial Electronics*, Vol. 48, No. 2, pp. 309-321, April 2001.
- [2] Ziogas, Phoivas D., Eduardo P. Wiechmann, and Victor R. Stefanovic. "A Computer-Aided Analysis and Design Approach for Static Voltage Source Inverters." *IEEE Transactions on Industrial Electronics. Transactions on Industry Applications*, Vol. IA-21, No. 5, September/October 1985.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

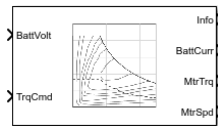
See Also

Flux-Based PM Controller | Induction Motor | Interior PMSM | Surface Mount PMSM

Mapped Motor

Mapped motor and drive electronics operating in torque-control mode

Library: Powertrain Blockset / Propulsion / Electric Motors and Inverters
Vehicle Dynamics Blockset / Powertrain / Propulsion



Description

The Mapped Motor block implements a mapped motor and drive electronics operating in torque-control mode. The output torque tracks the torque reference demand and includes a motor-response and drive-response time constant. Use the block for fast system-level simulations when you do not know detailed motor parameters, for example, for motor power and torque tradeoff studies. The block assumes that the speed fluctuations due to mechanical load do not affect the motor torque tracking.

You can specify:

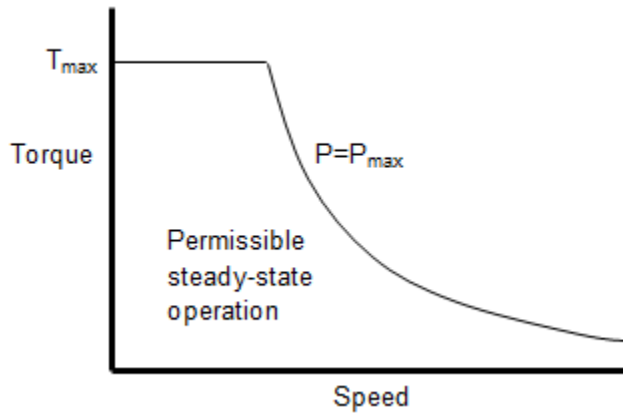
- Port configuration — Input torque or speed.
- Electrical torque range — Torque speed envelope or maximum motor power and torque.
- Electrical loss — Single operating point, measured efficiency, or measured loss. If you have Model-Based Calibration Toolbox, you can virtually calibrate the measured loss tables.

Electrical Torque

To specify the range of torque and speed that the block allows, on the **Electrical Torque** tab, for **Parametrized by**, select one of these options.

Setting	Block Implementation
Tabulated torque-speed envelope	Range specified as a set of speed data points and corresponding maximum torque values.
Maximum torque and power	Range specified with maximum torque and maximum power.

For either method, the block implements an envelope similar to this.



Electrical Losses

To specify the electrical losses, on the **Electrical Losses** tab, for **Parameterize losses by**, select one of these options.

Setting	Block Implementation
Single efficiency measurement	<p>Sum of these terms, measured at a single measurement point:</p> <ul style="list-style-type: none"> • Fixed losses independent of torque and speed, P_0. Use P_0 to account for fixed converter losses. • A torque-dependent electrical loss $k\tau^2$, where k is a constant and τ is the torque. Represents ohmic losses in the copper windings. • A speed-dependent electrical loss $k_w\omega^2$, where k_w is a constant and ω is the speed. Represents iron losses due to eddy currents.
Tabulated loss data	<p>Loss lookup table that is a function of motor speeds and load torques.</p> <p>If you have Model-Based Calibration Toolbox, click Calibrate Maps to virtually calibrate the 2D lookup tables using measured data.</p>
Tabulated loss data with temperature	<p>Loss lookup table that is a function of motor speeds, load torques, and operating temperature.</p> <p>If you have Model-Based Calibration Toolbox, click Calibrate Maps to virtually calibrate the 3D lookup tables using measured data.</p>

Setting	Block Implementation
Tabulated efficiency data	2D efficiency lookup table that is a function of motor speeds and load torques: <ul style="list-style-type: none"> • Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. • Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. • Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. • Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.
Tabulated efficiency data with temperature	3D efficiency lookup table that is a function of motor speeds, load torques, and operating temperature: <ul style="list-style-type: none"> • Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. • Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. • Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. • Does not extrapolate loss values for speed, torque, or temperature magnitudes that exceed the range of the table.

For best practice, use **Tabulated loss data** instead of **Tabulated efficiency data**:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Note Due to system losses, the motor can draw a current when the motor torque is zero.

Virtual Calibration

If you have Model-Based Calibration Toolbox, you can virtually calibrate the measured loss lookup tables.

- 1 On the **Electrical Losses** tab, set **Parameterize losses by** to either:
 - Tabulated loss data
 - Tabulated loss data with temperature
- 2 Click **Calibrate Maps**.

The dialog box steps through these tasks.

Task	Description						
Import Loss Data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autoblksshared/mbctemplates/MappedMotorDataset.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p>						
	<table border="1"> <thead> <tr> <th data-bbox="508 449 760 520">Parameterize losses by</th> <th data-bbox="760 449 1466 520">Required Data</th> </tr> </thead> <tbody> <tr> <td data-bbox="508 520 760 653">Tabulated loss data</td> <td data-bbox="760 520 1466 653"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W </td> </tr> <tr> <td data-bbox="508 653 760 821">Tabulated loss data with temperature</td> <td data-bbox="760 653 1466 821"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W </td> </tr> </tbody> </table>	Parameterize losses by	Required Data	Tabulated loss data	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 	Tabulated loss data with temperature	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W
	Parameterize losses by	Required Data					
	Tabulated loss data	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 					
Tabulated loss data with temperature	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W 						
<p>Collect motor data at steady-state operating conditions. Data should cover the motor speed, torque, and temperature operating range.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>							
Generate Response Models	<p>Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>						
Generate Calibration	<p>Model-Based Calibration Toolbox calibrates the response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>						

Task	Description	
Update block parameters	Update these parameters with the calibration.	
	Parameterize losses by	Parameters
	Tabulated loss data	<ul style="list-style-type: none"> • Vector of speeds(w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding losses, losses_table
Tabulated loss data with temperature	<ul style="list-style-type: none"> • Vector of speeds(w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, Temp_eff_bp • Corresponding losses, losses_table_3d 	

Battery Current

The block calculates the battery current using the mechanical power, power loss, and battery voltage. Positive current indicates battery discharge. Negative current indicates battery charge.

$$BattAmp = \frac{MechPwr + PwrLoss}{BattVolt}$$

The equation uses these variables.

- BattVolt* Battery voltage
- MechPwr* Mechanical power
- PwrLoss* Power loss
- BattCurr* Battery current

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrIn fo	PwrTrnsfrd	PwrMtr	Mechanical power	P_{mot}	$P_{mot} = \omega_m T_e$
	<ul style="list-style-type: none"> • Positive signals indicate power flow into the block. • Negative signals indicate power flow out of the block. 	PwrBus	Electrical power	P_{bus}	$P_{bus} = P_{mot} + P_{loss}$
	PwrNotTrnsfrd	PwrLoss	Motor power loss	P_{loss}	$P_{stored} = \omega_m \dot{\omega}_m J$
	<ul style="list-style-type: none"> • Negative signals indicate power loss. 				

Bus Signal		Description	Variable	Equations	
	PwrStored • Positive signals indicate power gain.	PwrStoredShft	Motor power stored	P_{str}	$P_{loss} = - (P_{mot} + P_{loss} - P_{stored})$

The equations use these variables.

T_e	Motor output shaft torque
ω	Motor shaft speed
J	Motor inertia

Ports

Input

BattVolt – Battery voltage
scalar

Battery voltage, *BattVolt*, in V.

TrqCmd – Commanded motor torque
scalar

Commanded motor torque, *TrqCmd*, in N·m.

Dependencies

To create this input port, for the **Port configuration**, select Torque.

MtrSpd – Motor output shaft speed
scalar

Motor shaft speed, *MtrSpd*, in rad/s.

Dependencies

To create this input port, for the **Port configuration**, select Speed.

Output

Info – Bus signal
bus

The bus signal contains these block calculations.

Signal		Description	Units	
MechPwr		Mechanical power	W	
PwrLoss		Internal inverter and motor power loss	N·m	
PwrInfo	PwrTrnsfrd	PwrMtr	Mechanical power	W
		PwrBus	Electrical power	W

Signal		Description	Units
	PwrNotTrnsfrd	PwrLoss	Motor power loss
	PwrStored	PwrStored Shft	Motor power stored

BattCurr – Battery current

scalar

Battery current draw or demand, I_{batt} , in A.

MtrTrq – Motor torque

scalar

Motor output shaft torque, Mtr_{trq} , in N·m.

MtrSpd – Motor shaft speed

scalar

Motor shaft speed, Mtr_{spd} , in rad/s.

Dependencies

To create this output port, for the **Port configuration**, select Torque.

Parameters

Block Options

Port configuration – Select port configuration

Torque (default) | Speed

This table summarizes the port configurations.

Port Configuration	Creates Ports
Torque	Outpost MtrSpd
Speed	Input MtrSpd

Calibrate Maps – Calibrate tables with measured data

selection

If you have Model-Based Calibration Toolbox, you can virtually calibrate the measured loss lookup tables.

- 1 On the **Electrical Losses** tab, set **Parameterize losses by** to either:
 - Tabulated loss data
 - Tabulated loss data with temperature
- 2 Click **Calibrate Maps**.

The dialog box steps through these tasks.

Task	Description						
Import Loss Data	<p>Import this loss data from a file. For example, open <code><matlabroot>/toolbox/autoblks/autoblksshared/mbctemplates/MappedMotorDataset.xlsx</code>.</p> <p>For more information, see “Using Data” (Model-Based Calibration Toolbox).</p> <table border="1" data-bbox="505 447 1472 823"> <thead> <tr> <th data-bbox="505 447 756 520">Parameterize losses by</th> <th data-bbox="756 447 1472 520">Required Data</th> </tr> </thead> <tbody> <tr> <td data-bbox="505 520 756 651">Tabulated loss data</td> <td data-bbox="756 520 1472 651"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W </td> </tr> <tr> <td data-bbox="505 651 756 823">Tabulated loss data with temperature</td> <td data-bbox="756 651 1472 823"> <ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W </td> </tr> </tbody> </table> <p>Collect motor data at steady-state operating conditions. Data should cover the motor speed, torque, and temperature operating range.</p> <p>To filter or edit the data, select Edit in Application. The Model-Based Calibration Toolbox Data Editor opens.</p>	Parameterize losses by	Required Data	Tabulated loss data	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 	Tabulated loss data with temperature	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W
Parameterize losses by	Required Data						
Tabulated loss data	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Power loss, W 						
Tabulated loss data with temperature	<ul style="list-style-type: none"> • Motor speed, rad/s • Motor torque, N·m • Motor temperature, K • Power loss, W 						
Generate Response Models	<p>Model-Based Calibration Toolbox uses test plans to fit data to Gaussian process models (GPMs).</p> <p>To assess or adjust the response model fit, select Edit in Application. The Model-Based Calibration Toolbox Model Browser opens. For more information, see “Model Assessment” (Model-Based Calibration Toolbox).</p>						
Generate Calibration	<p>Model-Based Calibration Toolbox calibrates the response models and generates calibrated tables.</p> <p>To assess or adjust the calibration, select Edit in Application. The Model-Based Calibration Toolbox CAGE Browser opens. For more information, see “Calibration Lookup Tables” (Model-Based Calibration Toolbox).</p>						

Task	Description	
Update block parameters	Update these parameters with the calibration.	
	Parameterize losses by	Parameters
	Tabulated loss data	<ul style="list-style-type: none"> • Vector of speeds(w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Corresponding losses, $losses_table$
Tabulated loss data with temperature	<ul style="list-style-type: none"> • Vector of speeds(w) for tabulated losses, w_eff_bp • Vector of torques (T) for tabulated losses, T_eff_bp • Vector of temperatures for tabulated losses, $Temp_eff_bp$ • Corresponding losses, $losses_table_3d$ 	

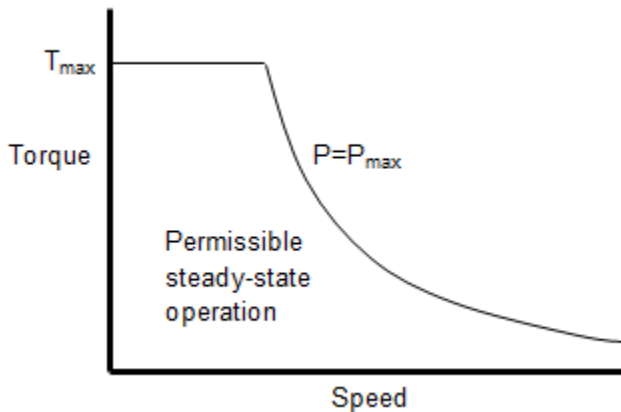
Electrical Torque

Parameterized by – Select type

Tabulated torque-speed envelope (default) | Maximum torque and power

Setting	Block Implementation
Tabulated torque-speed envelope	Range specified as a set of speed data points and corresponding maximum torque values.
Maximum torque and power	Range specified with maximum torque and maximum power.

For either method, the block implements an envelope similar to this.



Vector of rotational speeds, w_t – Rotational speeds

[0 375 750 800] (default) | vector

Rotational speeds for permissible steady-state operation, in rad/s. To avoid poor performance due to an infinite slope in the torque-speed curve, specify a vector of rotational speeds that does not contain duplicate consecutive values.

Dependencies

To create this parameter, for the **Parameterized by** parameter, select Tabulated torque-speed envelope.

Vector of maximum torque values, T_t – Torque

[0.09 0.08 0.07 0] (default) | vector

Maximum torque values for permissible steady state, in N·m.

Dependencies

To create this parameter, for the **Parameterized by** parameter, select Tabulated torque-speed envelope.

Maximum torque, torque_max – Torque

.1 (default) | scalar

The maximum permissible motor torque, in N·m.

Dependencies

To create this parameter, for the **Parameterized by** parameter, select Maximum torque and power.

Maximum power, power_max – Power

30 (default) | scalar

The maximum permissible motor power, in W.

Dependencies

To create this parameter, for the **Parameterized by** parameter, select Maximum torque and power.

Torque control time constant, T_c – Time constant

0.02 (default) | scalar

Time constant with which the motor driver tracks a torque demand, in s.

Electrical Losses**Parameterize losses by – Select type**

Single efficiency measurement (default) | Tabulated loss data | Tabulated efficiency data

Setting	Block Implementation
Single efficiency measurement	<p>Sum of these terms, measured at a single measurement point:</p> <ul style="list-style-type: none"> • Fixed losses independent of torque and speed, P_0. Use P_0 to account for fixed converter losses. • A torque-dependent electrical loss $k\tau^2$, where k is a constant and τ is the torque. Represents ohmic losses in the copper windings. • A speed-dependent electrical loss $k_w\omega^2$, where k_w is a constant and ω is the speed. Represents iron losses due to eddy currents.
Tabulated loss data	<p>Loss lookup table that is a function of motor speeds and load torques.</p> <p>If you have Model-Based Calibration Toolbox, click Calibrate Maps to virtually calibrate the 2D lookup tables using measured data.</p>
Tabulated loss data with temperature	<p>Loss lookup table that is a function of motor speeds, load torques, and operating temperature.</p> <p>If you have Model-Based Calibration Toolbox, click Calibrate Maps to virtually calibrate the 3D lookup tables using measured data.</p>
Tabulated efficiency data	<p>2D efficiency lookup table that is a function of motor speeds and load torques:</p> <ul style="list-style-type: none"> • Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. • Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. • Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. • Does not extrapolate loss values for speed and torque magnitudes that exceed the range of the table.

Setting	Block Implementation
Tabulated efficiency data with temperature	<p>3D efficiency lookup table that is a function of motor speeds, load torques, and operating temperature:</p> <ul style="list-style-type: none"> • Converts the efficiency values you provide into losses and uses the tabulated losses for simulation. • Ignores efficiency values you provide for zero speed or zero torque. Losses are assumed zero when either torque or speed is zero. • Uses linear interpolation to determine losses. Provide tabulated data for low speeds and low torques, as required, to get the desired level of accuracy for lower power conditions. • Does not extrapolate loss values for speed, torque, or temperature magnitudes that exceed the range of the table.

For best practice, use **Tabulated loss data** instead of **Tabulated efficiency data**:

- Efficiency becomes ill defined for zero speed or zero torque.
- You can account for fixed losses that are still present for zero speed or torque.

Note Due to system losses, the motor can draw a current when the motor torque is zero.

Motor and drive overall efficiency, **eff** – Efficiency

100 (default) | scalar

The block defines overall efficiency as:

$$\eta = 100 \frac{\tau_0 \omega_0}{\tau_0 \omega_0 + P_0 + k \tau_0^2 + k_w \omega_0^2}$$

The equation uses these variables.

τ_0	Torque at which efficiency is measured
ω_0	Speed at which efficiency is measured
P_0	Fixed losses independent of torque or speed
$k \tau_0^2$	Torque-dependent electrical losses
$k_w \omega_0^2$	Speed-dependent iron losses

At initialization, the block solves the efficiency equation for k . The block neglects losses associated with the rotor damping.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select **Single efficiency measurement**.

Speed at which efficiency is measured, **w_eff** – Speed

375 (default) | scalar

Speed at which efficiency is measured, in rad/s.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select **Single efficiency measurement**.

Torque at which efficiency is measured, T_{eff} – Torque

0.08 (default) | scalar

Torque at which efficiency is measured, in N·m.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select **Single efficiency measurement**.

Iron losses, P_{iron} – Power

0 (default) | scalar

Iron losses at the speed and torque at which efficiency is defined, in W.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select **Single efficiency measurement**.

Fixed losses independent of torque and speed, P_{base} – Power

0 (default) | scalar

Fixed electrical loss associated with the driver when the motor current and torque are zero, in W.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select **Single efficiency measurement**.

Vector of speeds (w) for tabulated losses, $w_{\text{eff_bp}}$ – Breakpoints

[-8000 -4000 0 4000 8000] (default) | 1-by-M vector

Speed breakpoints for lookup table when calculating losses, in rad/s. Array dimensions are 1 by the number of speed breakpoints, M.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select one of these:

- Tabulated loss data
- Tabulated loss data with temperature
- Tabulated efficiency data
- Tabulated efficiency data with temperature

Vector of torques (T) for tabulated losses, $T_{\text{eff_bp}}$ – Breakpoints

[0 0.03 0.06 0.09] (default) | 1-by-N vector

Torque breakpoints for lookup table when calculating losses, in N·m. Array dimensions are 1 by the number of torque breakpoints, N.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select one of these:

- Tabulated loss data
- Tabulated loss data with temperature
- Tabulated efficiency data
- Tabulated efficiency data with temperature

Vector of temperatures for tabulated losses, Temp_eff_bp – Breakpoints

[233.15 293.15 373.15] (default) | 1-by-L vector

Temperature breakpoints for lookup table when calculating losses, in K. Array dimensions are 1 by the number of temperature breakpoints, L.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select one of these:

- Tabulated loss data with temperature
- Tabulated efficiency data with temperature

Corresponding losses, losses_table – 2D lookup table

M-by-N matrix

Array of values for electrical losses as a function of speed and torque, in W. Each value specifies the losses for a specific combination of speed and torque. The array dimensions must match the speed, M, and torque, N, breakpoint vector dimensions.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select Tabulated loss data.

Corresponding losses, losses_table_3d – 3D lookup table

M-by-N-by-L array

Array of values for electrical losses as a function of speed, torque, and temperature, in W. Each value specifies the losses for a specific combination of speed, torque, and temperature. The array dimensions must match the speed, M, torque, N, and temperature, L, breakpoint vector dimensions.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select Tabulated loss data with temperature.

Corresponding efficiency, efficiency_table – 2D lookup table

M-by-N matrix

Array of efficiency as a function of speed and torque, in %. Each value specifies the losses for a specific combination of speed and torque. The array dimensions must match the speed, M, and torque, N, breakpoint vector dimensions.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select Tabulated efficiency data.

Corresponding efficiency, `efficiency_table_3d` – 3D lookup table

M-by-N-by-L array

Array of efficiency as a function of speed and torque, in %. Each value specifies the losses for a specific combination of speed and torque. The array dimensions must match the speed, M, torque, N, and temperature, L, breakpoint vector dimensions.

The block ignores efficiency values for zero speed or zero torque. Losses are zero when either torque or speed is zero. The block uses linear interpolation.

To get the desired level of accuracy for lower power conditions, you can provide tabulated data for low speeds and low torques.

Dependencies

To create this parameter, for the **Parameterize losses by** parameter, select Tabulated efficiency data.

Mechanical

Rotor inertia, `J` – Inertia

5e-6 (default) | scalar

Rotor resistance to change in motor motion, in kg*m². The value can be zero.

Dependencies

To create this parameter, for the **Port configuration** parameter, select Torque.

Rotor damping, `b` – Damping

1e-5 (default) | scalar

Rotor damping, in N·m/(rad/s). The value can be zero.

Dependencies

To create this parameter, for the **Port configuration** parameter, select Torque.

Initial rotor speed, `omega_o` – Speed

0 (default) | scalar

Rotor speed at the start of the simulation, in rad/s.

Dependencies

To create this parameter, for the **Port configuration** parameter, select Torque.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

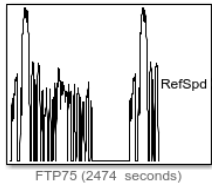
Flux-Based PMSM | Induction Motor | Interior PMSM | Surface Mount PMSM

Scenario Creation Blocks

Drive Cycle Source

Standard or specified longitudinal drive cycle

Library: Powertrain Blockset / Vehicle Scenario Builder
Vehicle Dynamics Blockset / Vehicle Scenarios / Drive Cycle and Maneuvers



Description

The Drive Cycle Source block generates a standard or user-specified longitudinal drive cycle. The block output is the specified vehicle longitudinal speed, which you can use to:

- Predict the engine torque and fuel consumption that a vehicle requires to achieve desired speed and acceleration for a given gear shift reference.
- Produce realistic velocity and shift references for closed loop acceleration and braking commands for vehicle control and plant models.
- Study, tune, and optimize vehicle control, system performance, and system robustness over multiple drive cycles.
- Identify the faults within tolerances specified by standardized tests, including:
 - EPA dynamometer driving schedules¹
 - Worldwide Harmonised Light Vehicle Test Procedure (WLTP) laboratory tests²

For the drive cycles, you can use:

- Drive cycles from predefined sources. By default, the block includes the FTP–75 drive cycle. To install additional drive cycles from a support package, see “Install Drive Cycle Data”. The support package has drive cycles that include the gear shift schedules, for example JC08 and CUEDC.
- Workspace variables that define your own drive cycles.
- .mat, .xls, .xlsx, or .txt files.
- Wide open throttle (WOT) parameters, including initial and nominal reference speed, deceleration start time, and final reference speed.

To achieve the goals listed in the table, use the specified Drive Cycle Source block parameter options.

Goal	Action
Repeat the drive cycle if the simulation run time exceeds the drive cycle length.	Select Repeat cyclically .

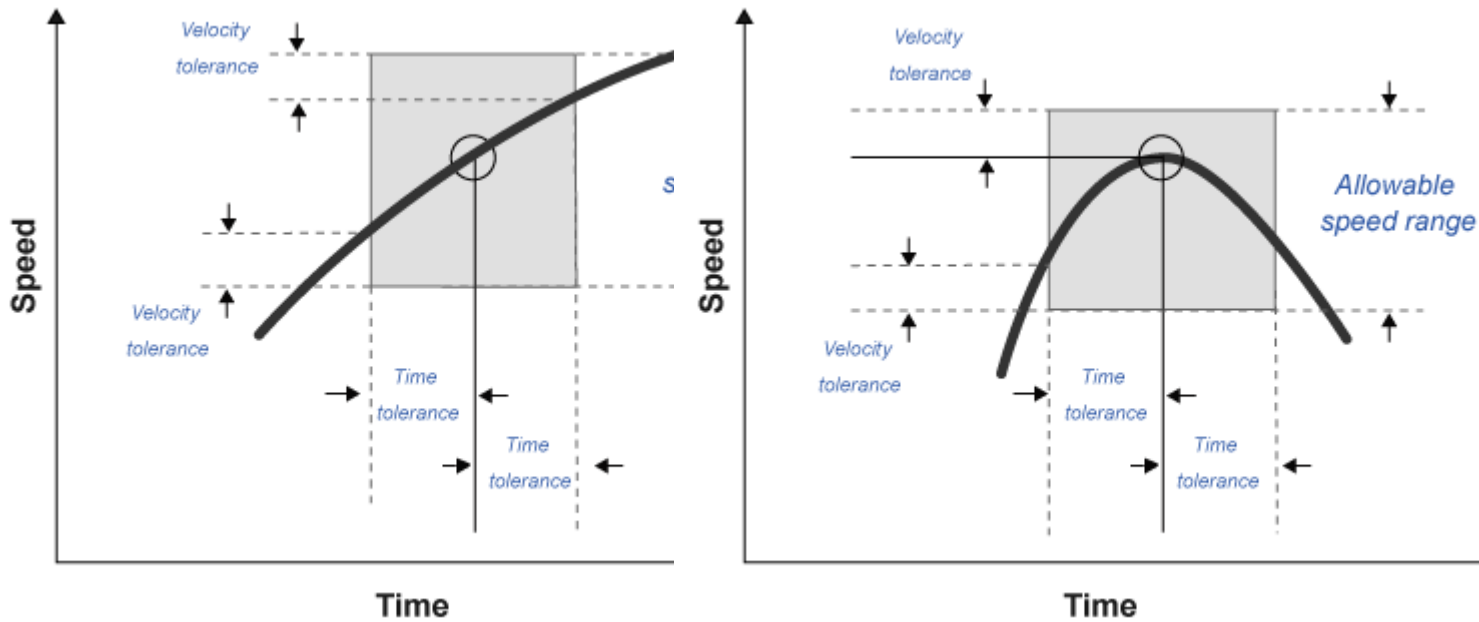
Goal	Action
Output the acceleration, as calculated by Savitzky-Golay differentiation.	Select Output acceleration .
Specify a sample period for discrete applications.	Specify a Output sample period (0 for continuous) , dt parameter.
Update the simulation run time so that it equals the length of the drive cycle.	Click Update simulation time . If a model configuration reference exists, the block does not enable this option.
Plot the drive cycle in a MATLAB® figure.	Click Plot drive cycle .
Specify the drive cycle using a workspace variable.	Click Specify variable . The block: <ul style="list-style-type: none"> • Sets the Drive cycle source parameter to Workspace variable. • Enables the From workspace parameter. Specify the workspace variable so that it contains time, velocity, and, optionally, the gear shift schedule. For examples, see “Create Drive Cycles Using Workspace Variables” on page 6-5.
Specify the drive cycle using a file.	Click Select file . The block: <ul style="list-style-type: none"> • Sets the Drive cycle source parameter to .mat, .xls, .xlsx or .txt file. • Enables the Drive cycle source file parameter. Specify a file that contains time, velocity, and, optionally, the gear shift schedule.
Output drive cycle gear.	Specify a drive cycle that contains a gear shift schedule. You can use: <ul style="list-style-type: none"> • A support package to install standard drive cycles that include the gear shift schedules, for example JC08 and CUEDC. • Workspace variables. • .mat, .xls, .xlsx, or .txt files. Click Output gear shift data .
Install additional drive cycles from a support package.	Click Install additional drive cycles . The block enables the parameter if you can install additional drive cycles from a support package.
Identify drive cycle faults within tolerances specified by standardized tests.	On the Fault Tracking tab, use the parameters to specify the fault tolerances. If the vehicle speed is not within the allowable speed range, the block sets a fault condition.

Fault and Failure Tracking

On the **Fault Tracking** tab, use the parameters to specify the fault tolerances. If the vehicle speed or time is not within the allowable range, the block sets a fault condition.

Parameter	Description	Setting	
		EPA Standard ¹	WLTP Tests ²
Speed tolerance	Speed tolerance above the highest point and below the lowest point of the drive cycle speed trace within the time tolerance.	2.0 mph	2.0 km/h
Time tolerance	Time that the block uses to determine the speed tolerance.	1.0 s	1.0 s
Maximum number of faults	Maximum number of faults during the drive cycle.	<i>Not specified</i>	10
Maximum single fault time	Maximum fault duration.	2.0 s	1.0 s
Maximum total fault time	Maximum accumulated time spent under fault condition.	<i>Not specified</i>	<i>Not specified</i>

These figures illustrate how the block uses the velocity and time tolerances to determine the allowable speed range.

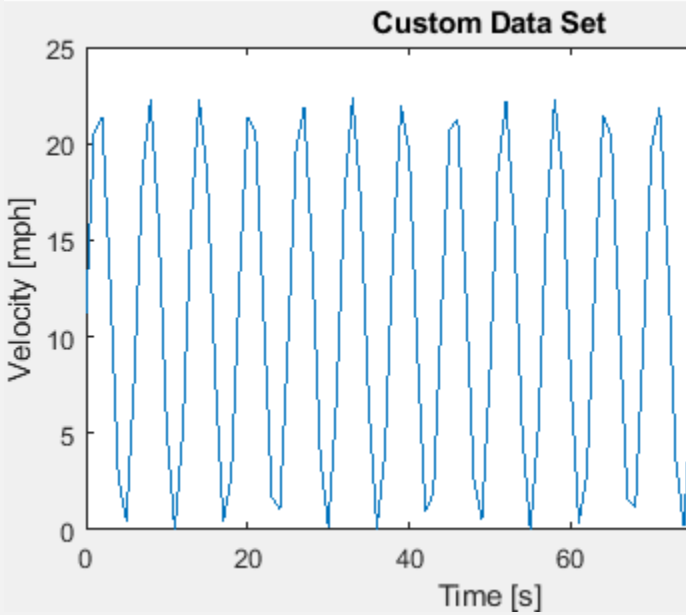
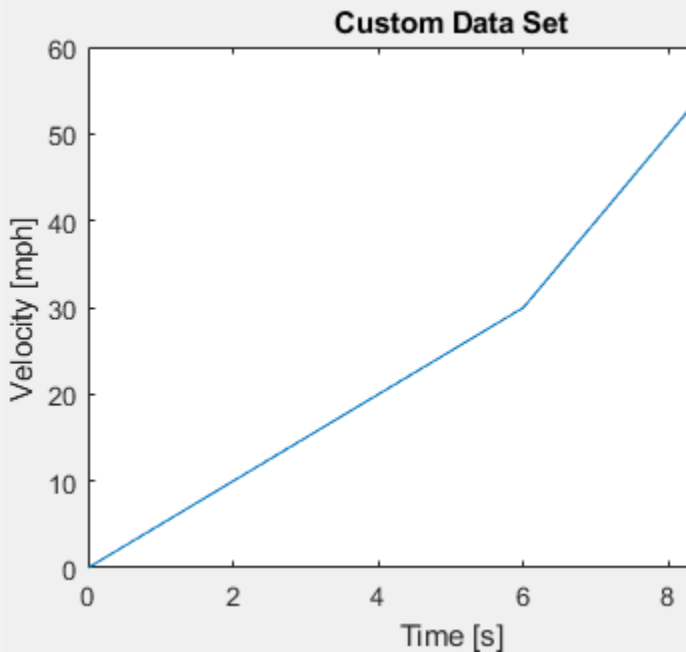


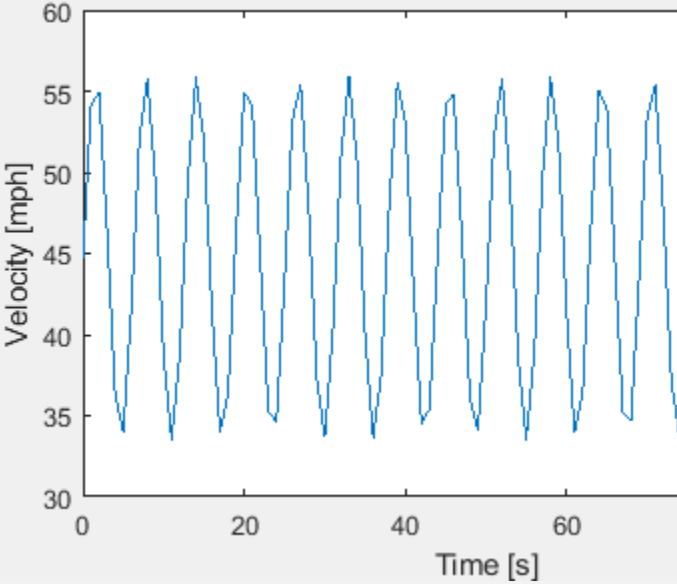
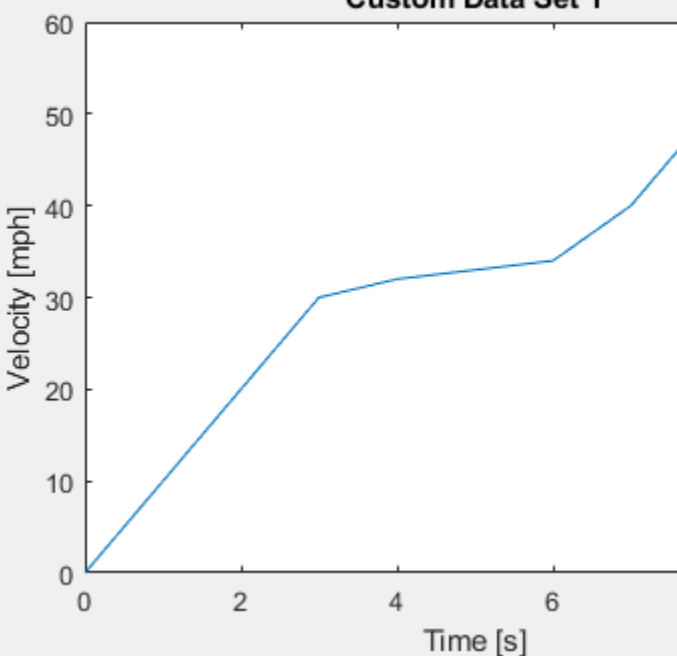
Create Drive Cycles Using Workspace Variables

If you set **Drive cycle source** to `Workspace variable`, you can specify a workspace variable that defines the drive cycle.

This table provides examples for using workspace variables to create your own drive cycles.

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
Structure without a gear shift schedule. From workspace set to <code>myCycleS</code> . <pre>t = 0:1:100; xdot = 5.*sin(t)+10; myCycleS.time = t'; myCycleS.signals.values = xdot';</pre>	m/s	mph	
Structure with a gear shift schedule. From workspace set to <code>myCycleS</code> . <pre>gears=[0, 1, 2, 3, 3, 4, 4, 4, 4, 4, 4]; t=0:1:10; xdot=[0,5,10,15,20,25,30,30,30,30,30]; myCycleS.time=t'; myCycleS.signals.values=[xdot',gears'];</pre>	m/s	mph	

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>2-D array without a gear shift schedule. From workspace set to myCycleA.</p> <pre>t = 0:1:100; xdot = 5.*sin(t)+5; myCycleA = [t',xdot'];</pre>	m/s	mph	
<p>2-D array with a gear shift schedule. From workspace set to myCycleA.</p> <pre>gears=[0, 1, 2, 3, 4, 4, 4, 5, 5, 5, 5]; t=0:1:10; xdot=[0,5,10,15,20,25,30,40,50,60,60]; myCycleA=[t',xdot',gears'];</pre>	mph	mph	

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>Time series object without a gear shift schedule. From workspace set to myCycleT.</p> <pre>myCycleT = timeseries; t = 0:1:100; xdot = 5.*sin(t)+20; myCycleT.Data = xdot'; myCycleT.Time = t;</pre>	m/s	mph	
<p>Time series object without a gear shift schedule. From workspace set to myCycleT.</p> <pre>myCycleT = timeseries; gears=[0, 1, 2, 3, 4, 4, 4, 5, 5, 5, 5]; t=0:1:10; xdot=[0,10,20,30,32,33,34,40,50,60,60]; myCycleT.Data = [xdot',gears']; myCycleT.Time = t';</pre>	mph	mph	

Ports

Input

VelFdbk — Vehicle longitudinal speed
scalar

Longitudinal vehicle speed.

Dependencies

To enable this port, on the **Fault Tracking** tab, select **Enable fault tracking**. Set the **Velocity feedback units, inUnit** parameter to the VelFdbk input port signal units.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description
Reference Spd		Vehicle reference speed
Reference Accel		Vehicle reference acceleration
Gear		Vehicle gear
Fault	UpprBnd	Upper bound of allowable vehicle speed range.
	LowerBnd	Lower bound of allowable vehicle speed range.
	Fault	Boolean value indicating fault condition: <ul style="list-style-type: none"> • 1 — Fault • 0 — No fault If the vehicle speed is not within the allowable speed range, the block sets a fault condition.
	FaultCnt	Number of faults.
	CumFaultTime	Cumulative time spent in fault condition.
	SnglFaultTime	Tim spent in a single fault.
	Fail	Boolean value indicating fault failure: <ul style="list-style-type: none"> • 1 — Failure • 0 — No failure If the fault conditions exceed the maximum number of faults, maximum single fault time, or maximum total fault time, the block sets a fault failure.

Dependencies

To enable this port, on the **Fault Tracking** tab, select **Enable fault tracking**.

RefSpd — Vehicle reference speed

scalar

Vehicle reference speed, in units that you specify. To specify the units, use the **Output velocity units** parameter.

RefAcc — Vehicle reference acceleration

scalar

To calculate the acceleration, the block implements Savitzky-Golay differentiation using a second-order polynomial with a three-sample point filter.

Dependencies

To create the output acceleration port, select **Output acceleration**. Selecting **Output acceleration** enables the **Output acceleration units** parameter.

Gear — Vehicle gear

scalar

Dependencies

To enable this port:

- 1 Specify a drive cycle that contains a gear shift schedule. You can use:
 - A support package to install standard drive cycles that include the gear shift schedules, for example JC08 and CUEDC.
 - Workspace variables.
 - `.mat`, `.xls`, `.xlsx`, or `.txt` files.
- 2 Select **Output gear shift** data.

Parameters

Cycle Setup

Setup

Drive cycle source — Select the drive cycle source

FTP75 (default) | Wide Open Throttle (WOT) | Workspace variable | `.mat`, `.xls`, `.xlsx` or `.txt` file

- **FTP75** — Load the FTP75 drive cycle from a `.mat` file into a 1-D Lookup Table block. The FTP75 represents a city drive cycle that you can use to determine tailpipe emissions and fuel economy of passenger cars. To install additional drive cycles from a support package, see “Install Drive Cycle Data”.
- **Wide Open Throttle (WOT)** — Use WOT parameters to specify a drive cycle for performance testing.
- **Workspace variable** — Specify time, speed, and, optionally, gear data as a structure, 2-D array, or time series object.
- **`.mat`, `.xls`, `.xlsx` or `.txt` file** — Specify a file that contains time, speed and, optionally, gear data in column format.

Once you have installed additional cycles, you can use `set_param` to set the drive cycle. For example, to use drive cycle US06:

```
set_param([gcs '/Drive Cycle Source'],'cycleVar','US06')
```

Dependencies

The table summarizes the parameter dependencies.

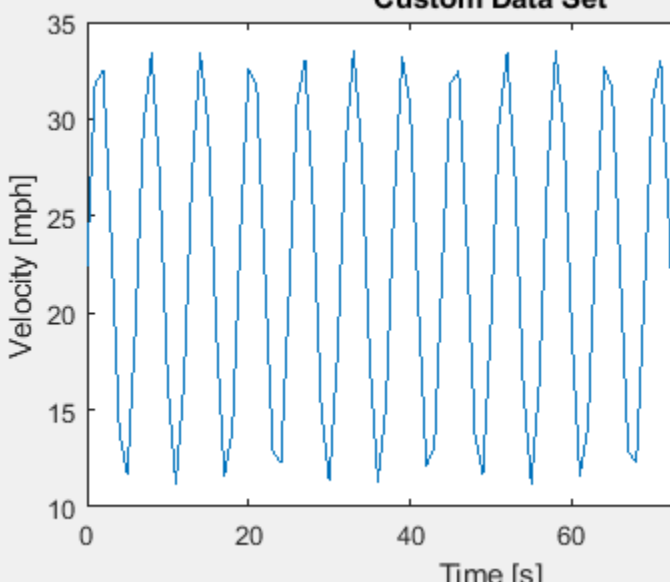
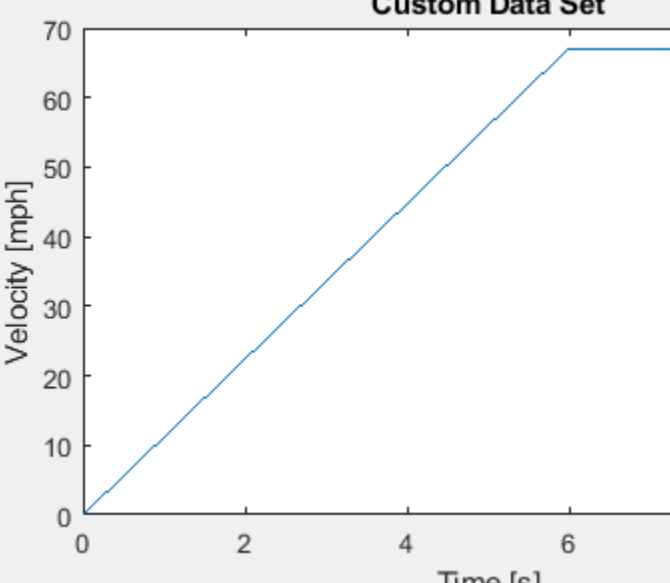
Drive Cycle Source	Enables Parameter
Wide Open Throttle (WOT)	Start time, <code>t_wot1</code>
	Initial reference speed, <code>xdot_woto</code>
	Nominal reference speed, <code>xdot_wot1</code>
	Time to start deceleration, <code>wot2</code>
	Final reference speed, <code>xdot_wot2</code>
	WOT simulation time, <code>t_wotend</code>
	Source velocity units
Workspace variable	From workspace
	Source velocity units
	Output gear shift data, if drive cycle includes gear shift schedule
.mat, .xls, .xlsx or .txt file	Drive cycle source file
	Source velocity units
	Output gear shift data, if drive cycle includes gear shift schedule

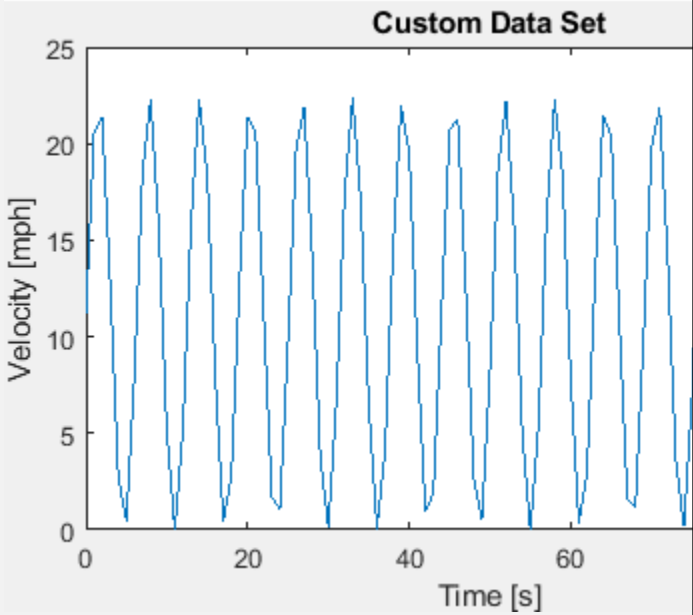
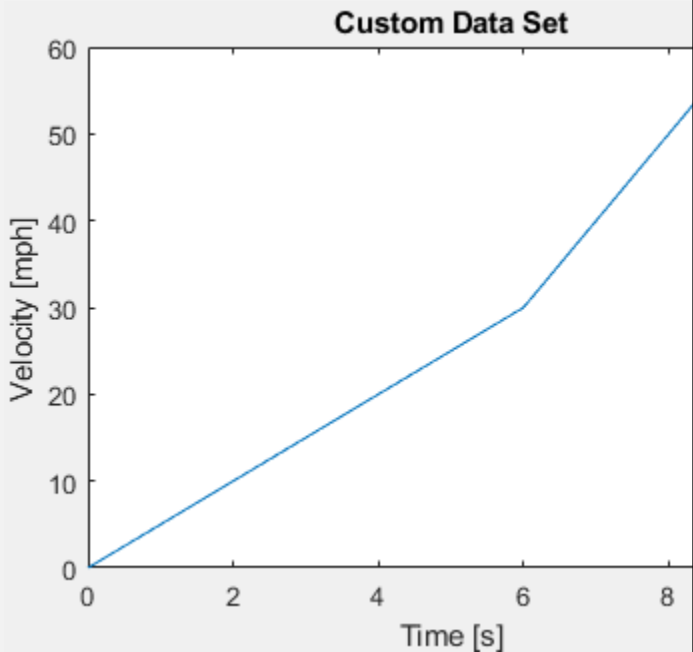
From workspace – Workspace variable

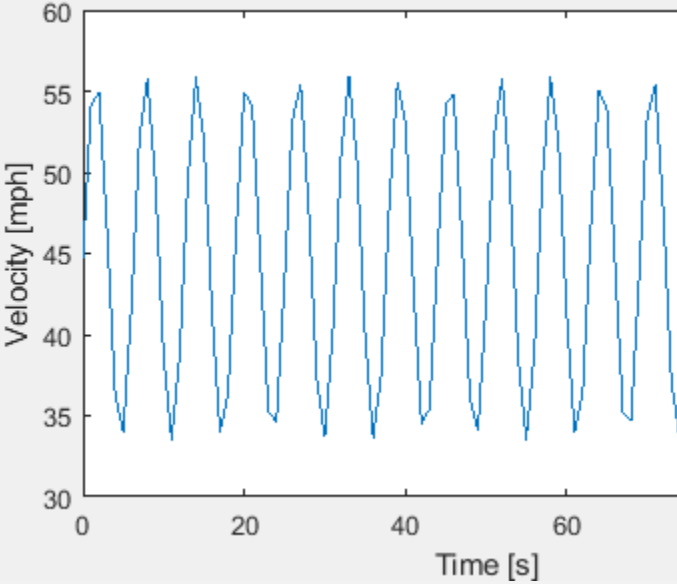
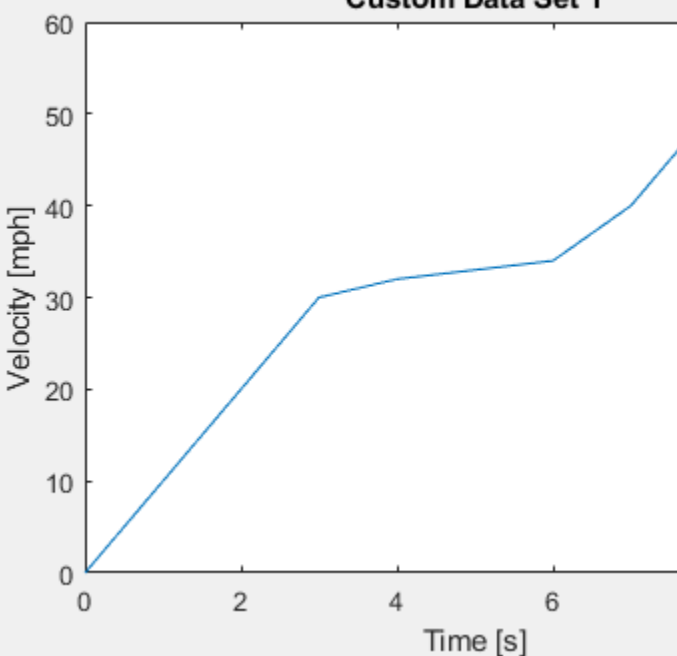
Monotonically increasing time, velocity, and, optionally, gear data, specified by a structure, 2-D array, or time series object. Enter units for velocity in the **Source velocity units** parameter field.

A valid point must exist for each corresponding time value. You cannot specify `inf`, `empty`, or `NaN`.

This table provides examples for using workspace variables to create your own drive cycles.

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>Structure without a gear shift schedule. From workspace set to myCycleS.</p> <pre>t = 0:1:100; xdot = 5.*sin(t)+10; myCycleS.time = t'; myCycleS.signals.values = xdot';</pre>	m/s	mph	
<p>Structure with a gear shift schedule. From workspace set to myCycleS.</p> <pre>gears=[0, 1, 2, 3, 3, 4, 4, 4, 4, 4, 4]; t=0:1:10; xdot=[0,5,10,15,20,25,30,30,30,30,30]; myCycleS.time=t'; myCycleS.signals.values=[xdot',gears'];</pre>	m/s	mph	

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>2-D array without a gear shift schedule. From workspace set to myCycleA.</p> <pre>t = 0:1:100; xdot = 5.*sin(t)+5; myCycleA = [t',xdot'];</pre>	m/s	mph	
<p>2-D array with a gear shift schedule. From workspace set to myCycleA.</p> <pre>gears=[0, 1, 2, 3, 4, 4, 4, 5, 5, 5, 5]; t=0:1:10; xdot=[0,5,10,15,20,25,30,40,50,60,60]; myCycleA=[t',xdot',gears'];</pre>	mph	mph	

Workspace Variable	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>Time series object without a gear shift schedule. From workspace set to myCycleT.</p> <pre>myCycleT = timeseries; t = 0:1:100; xdot = 5.*sin(t)+20; myCycleT.Data = xdot'; myCycleT.Time = t;</pre>	m/s	mph	
<p>Time series object without a gear shift schedule. From workspace set to myCycleT.</p> <pre>myCycleT = timeseries; gears=[0, 1, 2, 3, 4, 4, 4, 5, 5, 5, 5]; t=0:1:10; xdot=[0,10,20,30,32,33,34,40,50,60,60]; myCycleT.Data = [xdot',gears']; myCycleT.Time = t';</pre>	mph	mph	

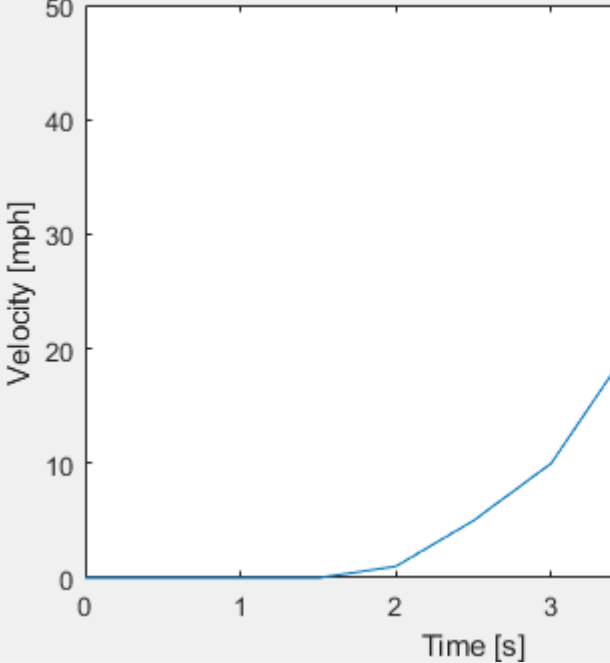
Dependencies

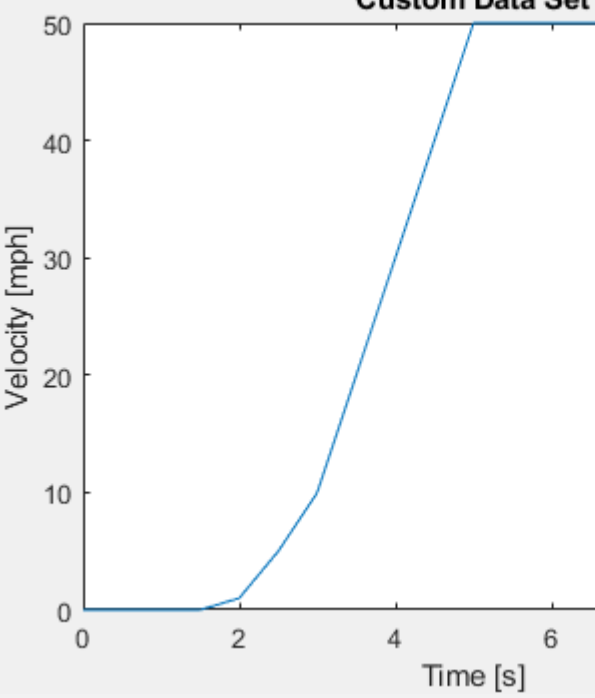
To enable this parameter, select Workspace variable from **Drive cycle source**.

Drive cycle source file – File name

.mat, .xls, .xlsx or .txt

File containing monotonically increasing time, velocity, and, optionally, gear in column or comma-separated format. The block ignores units in the file. Enter units for velocity in the **Source velocity units** parameter field.

File	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot																																				
<p>An .xls or .xlsx file with time in column A and velocity in column B.</p> <table border="1" data-bbox="241 667 467 1024"> <thead> <tr> <th></th> <th>A</th> <th>B</th> </tr> </thead> <tbody> <tr><td>1</td><td>0</td><td>0</td></tr> <tr><td>2</td><td>0.5</td><td>0</td></tr> <tr><td>3</td><td>1</td><td>0</td></tr> <tr><td>4</td><td>1.5</td><td>0</td></tr> <tr><td>5</td><td>2</td><td>1</td></tr> <tr><td>6</td><td>2.5</td><td>5</td></tr> <tr><td>7</td><td>3</td><td>10</td></tr> <tr><td>8</td><td>3.5</td><td>20</td></tr> <tr><td>9</td><td>4</td><td>30</td></tr> <tr><td>10</td><td>4.5</td><td>40</td></tr> <tr><td>11</td><td>5</td><td>50</td></tr> </tbody> </table>		A	B	1	0	0	2	0.5	0	3	1	0	4	1.5	0	5	2	1	6	2.5	5	7	3	10	8	3.5	20	9	4	30	10	4.5	40	11	5	50	mph	mph	<p style="text-align: center;">Custom Data Set</p> 
	A	B																																					
1	0	0																																					
2	0.5	0																																					
3	1	0																																					
4	1.5	0																																					
5	2	1																																					
6	2.5	5																																					
7	3	10																																					
8	3.5	20																																					
9	4	30																																					
10	4.5	40																																					
11	5	50																																					

File	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot																																																				
<p>An .xls or .xlsx file with time in column A, velocity in column B, and gear in column C. The block:</p> <ul style="list-style-type: none"> • Ignores the units in the file. • Converts the gear information to integers: <ul style="list-style-type: none"> • N to 0 • D to 2 <table border="1" data-bbox="240 772 576 1171"> <thead> <tr> <th></th> <th>A</th> <th>B</th> <th>C</th> </tr> </thead> <tbody> <tr> <td>1</td> <td>sec</td> <td>mph</td> <td>gear</td> </tr> <tr> <td>2</td> <td>0</td> <td>0</td> <td>N</td> </tr> <tr> <td>3</td> <td>0.5</td> <td>0</td> <td>N</td> </tr> <tr> <td>4</td> <td>1</td> <td>0</td> <td>N</td> </tr> <tr> <td>5</td> <td>1.5</td> <td>0</td> <td>N</td> </tr> <tr> <td>6</td> <td>2</td> <td>1</td> <td>D</td> </tr> <tr> <td>7</td> <td>2.5</td> <td>5</td> <td>D</td> </tr> <tr> <td>8</td> <td>3</td> <td>10</td> <td>D</td> </tr> <tr> <td>9</td> <td>3.5</td> <td>20</td> <td>D</td> </tr> <tr> <td>10</td> <td>4</td> <td>30</td> <td>D</td> </tr> <tr> <td>11</td> <td>4.5</td> <td>40</td> <td>D</td> </tr> <tr> <td>12</td> <td>5</td> <td>50</td> <td>D</td> </tr> </tbody> </table>		A	B	C	1	sec	mph	gear	2	0	0	N	3	0.5	0	N	4	1	0	N	5	1.5	0	N	6	2	1	D	7	2.5	5	D	8	3	10	D	9	3.5	20	D	10	4	30	D	11	4.5	40	D	12	5	50	D	mph	mph	<p>Custom Data Set</p> 
	A	B	C																																																				
1	sec	mph	gear																																																				
2	0	0	N																																																				
3	0.5	0	N																																																				
4	1	0	N																																																				
5	1.5	0	N																																																				
6	2	1	D																																																				
7	2.5	5	D																																																				
8	3	10	D																																																				
9	3.5	20	D																																																				
10	4	30	D																																																				
11	4.5	40	D																																																				
12	5	50	D																																																				

File	Source Velocity Unit	Output Velocity Unit	Drive Cycle Plot
<p>A .txt with time in column 1 and velocity in column 2. The block ignores the header and units information.</p> <pre> Time Speed sec mph 0 0 1 0 2 0 3 0 4 0 5 5 6 10 7 15 8 20 9 30 10 35 11 40 12 45 13 50 14 55 15 60 16 60 17 60 18 60 19 60 20 60 </pre>	mph	mph	

If you provide the gear schedule using **P, R, N, D, L, OD**, the block maps the gears to integers.

Gear	Integer
P	80
R	-1
N	0
L	1
D	2
OD	Next integer after highest specified gear.

For example, the block converts the gear schedule P P N L D 3 4 5 6 5 4 5 6 7 OD 7 to 80 80 0 1 2 3 4 5 6 5 4 5 6 7 8 7.

Dependencies

To enable this parameter, select **.mat, .xls, .xlsx or .txt** file from **Drive cycle source**.

Repeat cyclically – Repeat drive cycle

off (default) | on

Repeat the drive cycle if the simulation run time exceeds the length of the drive cycle.

Output acceleration — Output the acceleration

off (default)

To calculate the acceleration, the block implements Savitzky-Golay differentiation using a second-order polynomial with a three-sample point filter.

Dependencies

To create the output acceleration port, select **Output acceleration**. Selecting **Output acceleration** enables the **Output acceleration units** parameter.

Output gear shift data — Output the gear

off (default) | on

Dependencies

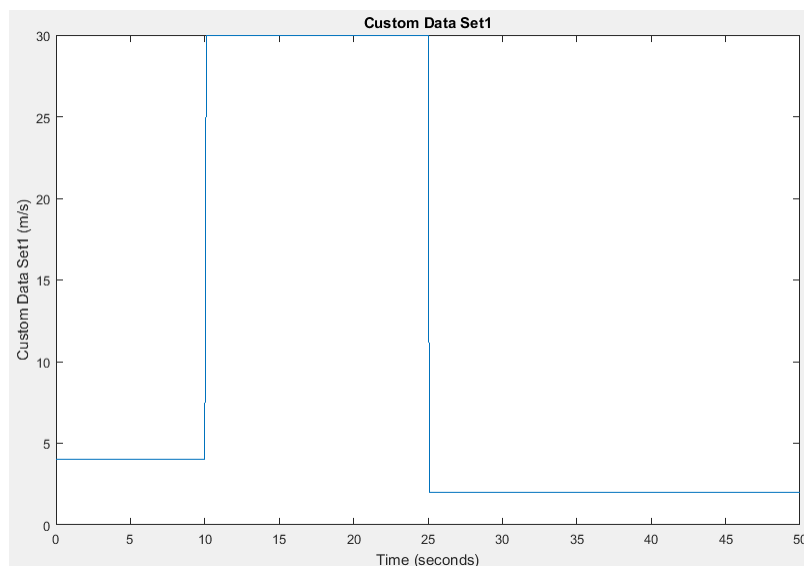
- Specify a drive cycle that contains a gear shift schedule. You can use:
 - A support package to install standard drive cycles that include the gear shift schedules, for example JC08 and CUEDC.
 - Workspace variables.
 - .mat, .xls, .xlsx, or .txt files.
- Clicking this parameter creates input port **Gear**.

WOT

Start time, t_wot1 — Drive cycle start time

5 (default) | scalar

Drive cycle start time, in s. For example, this plot shows a drive cycle with a start time of 10 s.

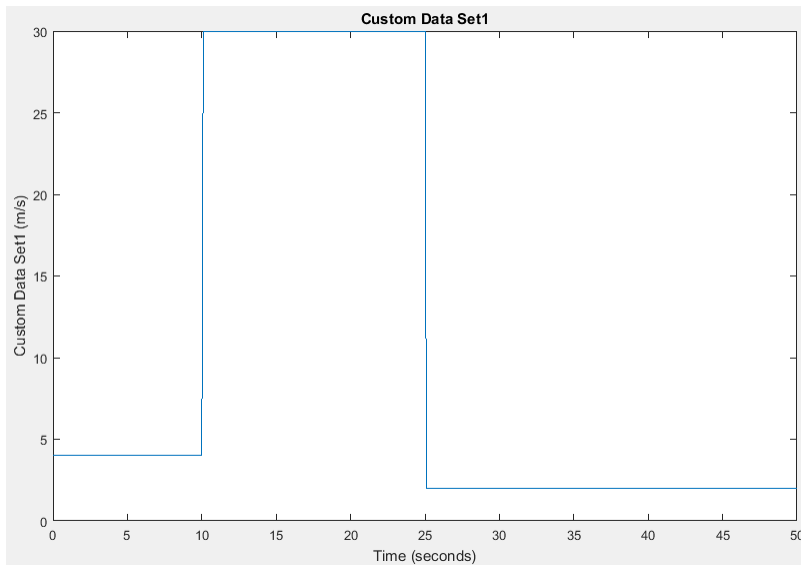


Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

Initial reference speed, xdot_woto – Speed 0 (default) | scalar

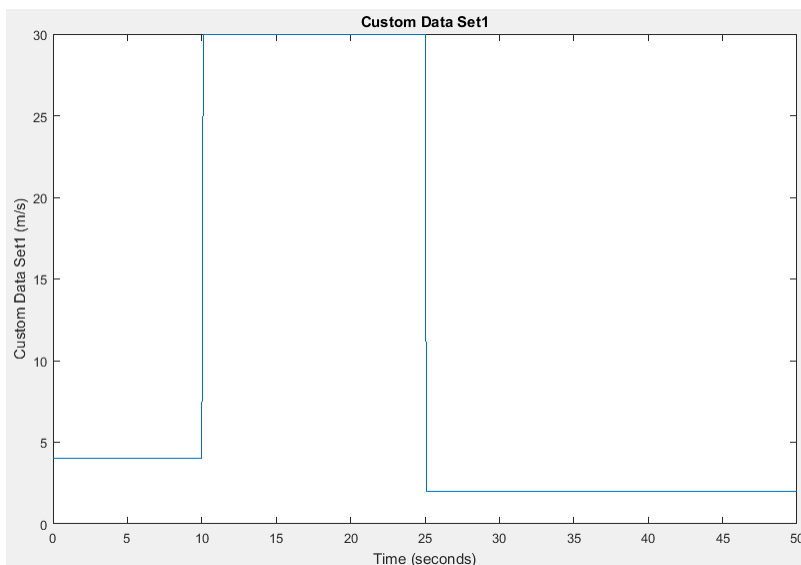
Initial reference speed, in units that you specify with the **Source velocity units** parameter. For example, this plot shows a drive cycle with an initial reference speed of 4 m/s.

**Dependencies**

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

Nominal reference speed, xdot_wot1 – Speed 30 (default) | scalar

Nominal reference speed, in units that you specify with the **Source velocity units** parameter. For example, this plot shows a drive cycle with a nominal reference speed of 30 m/s.



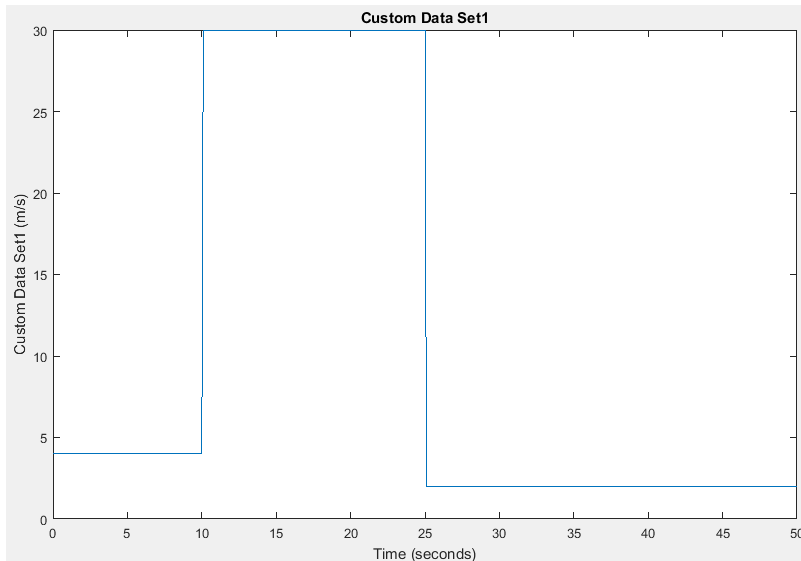
Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

Time to start deceleration, wot2 – Time

20 (default) | scalar

Time to start vehicle deceleration, in s. For example, this plot shows a drive cycle with vehicle deceleration starting at 25 s.



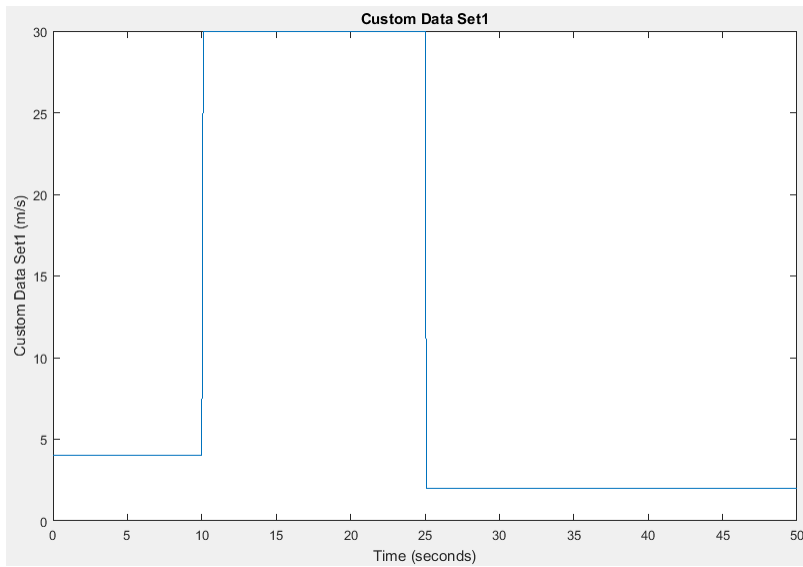
Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

Final reference speed, xdot_wot2 – Speed

0 (default) | scalar

Final reference speed, in units that you specify with the **Source velocity units** parameter. For example, this plot shows a drive cycle with a final reference speed of 2 m/s.



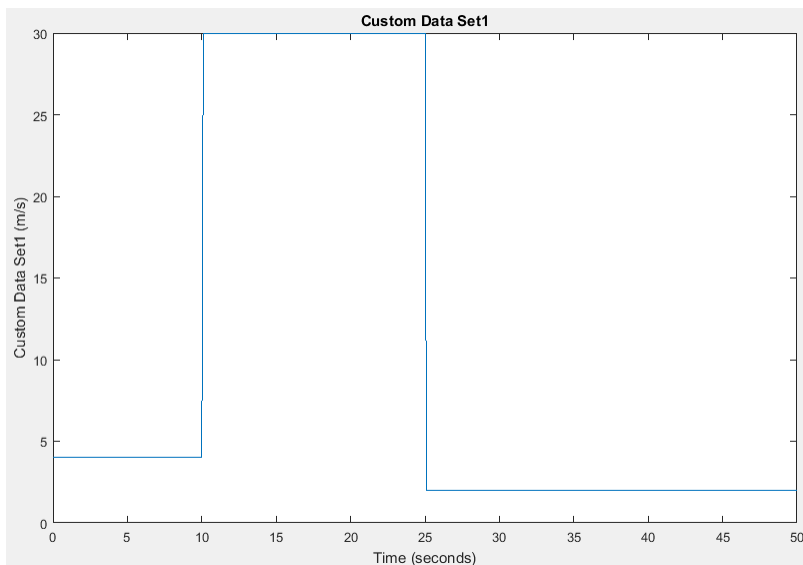
Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

WOT simulation time, t_{wotend} — Time

30 (default) | scalar

Drive cycle WOT simulation time, in s. For example, this plot shows a drive cycle with a simulation time of 50 s.



Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT).

Units and Sample Period

Source velocity units — Specify velocity units

m/s (default)

Input velocity units.

Dependencies

To enable this parameter, select the **Drive cycle source** parameter Wide Open Throttle (WOT), Workspace variable, or .mat, .xls, .xlsx or .txt file.

Output velocity units — Specify velocity units

m/s (default)

Output velocity units.

Output acceleration units — Specify acceleration units

m/s² (default)

Specify the output acceleration units.

Dependencies

To enable this parameter, select **Output acceleration**.

Output sample period (θ) for continuous — Sample rate

θ (default) | scalar

Sample rate. Set to θ for continuous sample period. For a discrete period, specify a non-zero rate.

Fault Tracking

Fault Settings

Enable fault tracking — Enable fault tracking

off (default) | on

Select this parameter to enable drive cycle fault tracking. Use the parameters to specify the fault tolerances. If the vehicle speed is not within the allowable speed range, the block sets a fault condition.

Dependencies

Selecting this parameter enables these parameters:

- **Speed tolerance, velBnd**
- **Speed tolerance units, velBndUnit**
- **Velocity feedback units, inUnit**
- **Time tolerance, timeBnd**

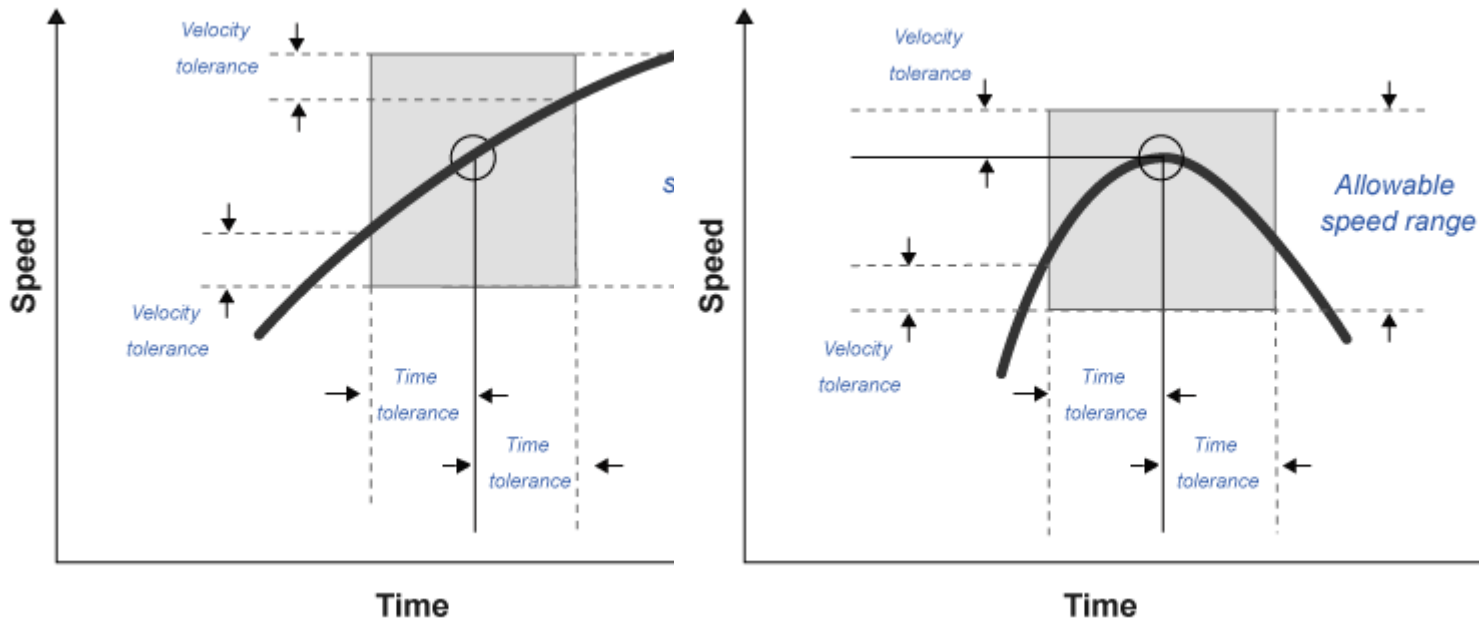
Speed tolerance, velBnd — Drive cycle speed tolerance

2.0 (default) | scalar

The speed tolerance above the highest point and below the lowest point of the drive cycle speed trace within the time tolerance. If the vehicle speed is not within the allowable speed range, the block sets a fault condition. For the tolerances specified by the standardized tests, use these settings:

- EPA dynamometer driving schedules — 2.0
- WLTP tests — 2.0

These figures illustrate how the block uses the velocity and time tolerances to determine the allowable speed range.



Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable fault tracking**.

Speed tolerance units, velBndUnit — Set units

mph (default)

Speed tolerance units. For the units specified by the standardized tests, use these units:

- EPA dynamometer driving schedules — m/s
- WLTP tests — km/h

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable fault tracking**.

Velocity feedback units, inUnit — Set velocity feedback units

m/s (default)

Velocity feedback units. Set the value to the VelFdbk input port signal units.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable fault tracking**.

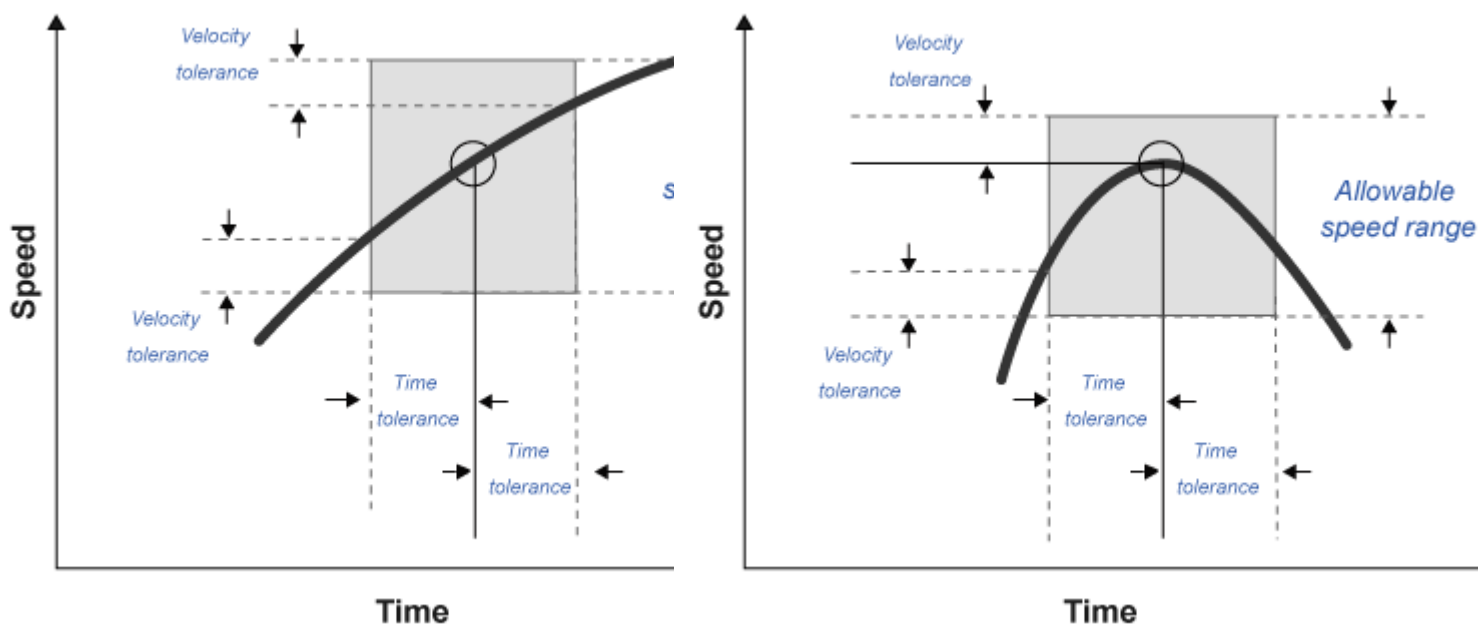
Time tolerance, timeBnd – Time tolerance

1.0 (default) | scalar

Time that the block uses to determine the speed tolerance. If the vehicle speed is not within the allowable speed range, the block sets a fault condition. For the time tolerances specified by the standardized tests, use these settings:

- EPA dynamometer driving schedules — 1.0
- WLTP tests — 1.0

These figures illustrate how the block uses the velocity and time tolerances to determine the allowable speed range.

**Dependencies**

To enable this parameter, on the **Fault Tracking** tab, select **Enable fault tracking**.

Failure Settings**Enable failure tracking – Enable failure tracking**

off (default) | on

Select this parameter to enable drive cycle failure tracking.

Dependencies

To enable this parameter, select **Enable fault tracking**. Selecting **Enable failure tracking** parameter enables these parameters:

- **Stop simulation when trace fails, stopSim**
- **Maximum number of faults, maxFaultCnt**

- **Maximum single fault time, maxFaultTime**
- **Maximum total fault time, maxTotFaultTime**

Maximum number of faults, maxFaultCnt — Maximum number of faults

10 (default) | scalar

Maximum number of faults during the drive cycle. For the number specified by the standardized tests, use these settings:

- EPA dynamometer driving schedules — *Not specified*
- WLTP tests — 10

If the number of faults exceeds the maximum number of faults, the block sets a fault failure.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable failure tracking**.

Maximum single fault time, maxFaultTime — Maximum duration of single fault

2.0 (default) | scalar

Maximum duration of single fault, in s. For the time specified by the standardized tests, use these settings:

- EPA dynamometer driving schedules — 2.0
- WLTP tests — 1.0

If the fault duration exceeds the maximum single fault time, the block sets a fault failure.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable failure tracking**.

Maximum total fault time, maxTotFaultTime — Maximum total fault time

15.0 (default) | scalar

Maximum accumulated time spent under fault condition, in s.

If the accumulated time spent under fault condition exceeds the maximum total fault time, the block sets a fault failure.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Enable failure tracking**.

Simulation Trace

Display simulation trace — Display velocity trace

off (default) | on

Select this parameter to display a velocity trace window. Selecting this parameter can slow the simulation time.

Dependencies

Selecting this parameter enables these parameters:

- **Simulation trace update rate, dtTrace**
- **Simulation trace display window, traceWindow**

Simulation trace update rate, dtTrace — Trace update rate

1 (default) | scalar

Simulation trace update rate, in s. Set to 0 for continuous sample period. For a discrete period, specify a non-zero rate.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Display simulation trace**.

Simulation trace display window, traceWindow — Trace window update rate

10 (default) | scalar

Simulation trace window update rate, in s.

Dependencies

To enable this parameter, on the **Fault Tracking** tab, select **Display simulation trace**.

Version History

Introduced in R2017a

References

[1] Environmental Protection Agency (EPA). *EPA urban dynamometer driving schedule*. 40 CFR 86.115-78, July 1, 2001.

[2] European Union Commission. "Speed trace tolerances". *European Union Commission Regulation*. 32017R1151, Sec 1.2.6.6, June 1, 2017.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

Longitudinal Driver

Topics

"Install Drive Cycle Data"

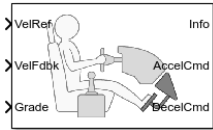
"Track Drive Cycle Errors"

"Time Series Objects and Collections"

Longitudinal Driver

Longitudinal speed-tracking controller

Library: Powertrain Blockset / Vehicle Scenario Builder
Vehicle Dynamics Blockset / Vehicle Scenarios / Driver



Description

The Longitudinal Driver block implements a longitudinal speed-tracking controller. Based on reference and feedback velocities, the block generates normalized acceleration and braking commands that can vary from 0 through 1. You can use the block to model the dynamic response of a driver or to generate the commands necessary to track a longitudinal drive cycle.

Configurations

External Actions

Use the **External Actions** parameters to create input ports for signals that can disable, hold, or override the closed-loop acceleration or deceleration commands. The block uses this priority order for the input commands: disable (highest), hold, override.

This table summarizes the external action parameters.

Goal	External Action Parameter	Input Ports	Data Type
Override the accelerator command with an input acceleration command.	Accelerator override	EnablAccelOvr	Boolean
		AccelOvrCmd	double
Hold the acceleration command at the current value.	Accelerator hold	AccelHld	Boolean
Disable the acceleration command.	Accelerator disable	AccelZero	Boolean
Override the decelerator command with an input deceleration command.	Decelerator override	EnablDecelOvr	Boolean
		DecelOvrCmd	double
Hold the decelerator command at current value.	Decelerator hold	DecelHld	Boolean
Disable the decelerator command.	Decelerator disable	DecelZero	Boolean

Controller

Use the **Control type**, **cntrlType** parameter to specify one of these control options.

Setting	Block Implementation
PI	Proportional-integral (PI) control with tracking windup and feed-forward gains.
Scheduled PI	PI control with tracking windup and feed-forward gains that are a function of vehicle velocity.
Predictive	<p>Optimal single-point preview (look ahead) control model developed by C. C. MacAdam^{1, 2, 3}. The model represents driver steering control behavior during path-following and obstacle avoidance maneuvers. Drivers preview (look ahead) to follow a predefined path. To implement the MacAdam model, the block:</p> <ul style="list-style-type: none"> • Represents the dynamics as a linear single track (bicycle) vehicle • Minimizes the previewed error signal at a single point T^* seconds ahead in time • Accounts for the driver lag deriving from perceptual and neuromuscular mechanisms

Shift

Use the **Shift type**, **shftType** parameter to specify one of these shift options.

Setting	Block Implementation
None	<p>No transmission. Block outputs a constant gear of 1.</p> <p>Use this setting to minimize the number of parameters you need to generate acceleration and braking commands to track forward vehicle motion. This setting does not allow reverse vehicle motion.</p>
Reverse, Neutral, Drive	<p>Block uses a Stateflow[®] chart to model reverse, neutral, and drive gear shift scheduling.</p> <p>Use this setting to generate acceleration and braking commands to track forward and reverse vehicle motion using simple reverse, neutral, and drive gear shift scheduling. Depending on the vehicle state and vehicle velocity feedback, the block uses the initial gear and time required to shift to shift the vehicle up into drive or down into reverse or neutral.</p> <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>

Setting	Block Implementation
Scheduled	<p>Block uses a Stateflow chart to model reverse, neutral, park, and N-speed gear shift scheduling.</p> <p>Use this setting to generate acceleration and braking commands to track forward and reverse vehicle motion using reverse, neutral, park, and N-speed gear shift scheduling. Depending on the vehicle state and vehicle velocity feedback, the block uses these parameters to determine the:</p> <ul style="list-style-type: none"> • Initial gear • Upshift and downshift accelerator pedal positions • Upshift and downshift velocity • Timing for shifting and engaging forward and reverse from neutral <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>
External	<p>Block uses the input gear, vehicle state, and velocity feedback to generate acceleration and braking commands to track forward and reverse vehicle motion.</p> <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>

Gear Signal

Use the **Output gear signal** parameter to create the GearCmd output port. The GearCmd signal contains the integer value of the commanded vehicle gear.

Gear	Integer
Park	80
Reverse	-1
Neutral	0
Drive	1
Gear	Gear number

Controller: PI Speed-Tracking

If you set the control type to PI or Scheduled PI, the block implements proportional-integral (PI) control with tracking windup and feed-forward gains. For the Scheduled PI configuration, the block uses feed forward gains that are a function of vehicle velocity.

To calculate the speed control output, the block uses these equations.

Setting	Equation
PI	$y = \frac{K_{ff}}{v_{nom}} v_{ref} + \frac{K_p e_{ref}}{v_{nom}} + \int \left(\frac{K_i e_{ref}}{v_{nom}} + K_{aw} e_{out} \right) dt + K_g \theta$

Setting	Equation
Scheduled PI	$y = \frac{K_{ff}(v)}{v_{nom}}v_{ref} + \frac{K_p(v)e_{ref}}{v_{nom}} + \int \left(\frac{K_i(v)e_{ref}}{v_{nom}} + K_{aw}e_{out} \right) e_{ref} dt + K_g(v)\theta$

where:

$$e_{ref} = v_{ref} - v$$

$$e_{out} = y_{sat} - y$$

$$y_{sat} = \begin{cases} -1 & y < -1 \\ y & -1 \leq y \leq 1 \\ 1 & 1 < y \end{cases}$$

The velocity error low-pass filter uses this transfer function.

$$H(s) = \frac{1}{\tau_{err}s + 1} \quad \text{for } \tau_{err} > 0$$

To calculate the acceleration and braking commands, the block uses these equations.

$$y_{acc} = \begin{cases} 0 & y_{sat} < 0 \\ y_{sat} & 0 \leq y_{sat} \leq 1 \\ 1 & 1 < y_{sat} \end{cases}$$

$$y_{dec} = \begin{cases} 0 & y_{sat} > 0 \\ -y_{sat} & -1 \leq y_{sat} \leq 0 \\ 1 & y_{sat} < -1 \end{cases}$$

The equations use these variables.

v_{nom}	Nominal vehicle speed
K_p	Proportional gain
K_i	Integral gain
K_{aw}	Anti-windup gain
K_{ff}	Velocity feed-forward gain
K_g	Grade angle feed-forward gain
θ	Grade angle
τ_{err}	Error filter time constant
y	Nominal control output magnitude
y_{sat}	Saturated control output magnitude
e_{ref}	Velocity error
e_{out}	Difference between saturated and nominal control outputs
y_{acc}	Acceleration signal
y_{dec}	Braking signal
v	Velocity feedback signal

v_{ref} Reference velocity signal

Controller: Predictive Speed-Tracking

If you set the **Control type**, **cntrlType** parameter to Predictive, the block implements an optimal single-point preview (look ahead) control model developed by C. C. MacAdam^{1, 2, 3}. The model represents driver steering control behavior during path-following and obstacle avoidance maneuvers. Drivers preview (look ahead) to follow a predefined path. To implement the MacAdam model, the block:

- Represents the dynamics as a linear single track (bicycle) vehicle
- Minimizes the previewed error signal at a single point T^* seconds ahead in time
- Accounts for the driver lag deriving from perceptual and neuromuscular mechanisms

Vehicle Dynamics

For longitudinal motion, the block implements these linear dynamics.

$$x_1 = v$$

$$\dot{x}_1 = x_2 = \frac{K_{pt}}{m} - g\sin(\gamma) + F_r x_1$$

In matrix notation:

$$\dot{x} = Fx + g\bar{u}$$

where:

$$x = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

$$F = \begin{bmatrix} 0 & 1 \\ \frac{F_r}{m} & 0 \end{bmatrix}$$

$$g = \begin{bmatrix} 0 \\ \frac{K_{pt}}{m} \end{bmatrix}$$

$$\bar{u} = u - \frac{m^2}{K_{pt}} g\sin(\gamma)$$

The block uses this equation for the rolling resistance.

$$F_r = - \left[\tanh(x_1) \left(\frac{a_r}{x_1} + c_r x_1 \right) + b_r \right]$$

The single-point model assumes a minimum previewed error signal at a single point T^* seconds ahead in time. a^* is the driver ability to predict the future vehicle response based on the current steering control input. b^* is the driver ability to predict the future vehicle response based on the current vehicle state. The block uses these equations.

$$a^* = (T^*)m^T \left[I + \sum_{n=1}^{\infty} \frac{F^n (T^*)^n}{(n+1)!} \right] g e$$

$$b^* = m^T \left[I + \sum_{n=1}^{\infty} \frac{F^n (T^*)^n}{n!} \right]$$

where:

$$m^T = [1 \ 1]$$

The equations use these variables.

a, b	Forward and rearward tire location, respectively
m	Vehicle mass
I	Vehicle rotational inertia
a^*, b^*	Driver prediction scalar and vector gain, respectively
\mathbf{x}	Predicted vehicle state vector
v	Longitudinal velocity
\mathbf{F}	System matrix
K_{pt}	Tractive force and brake limit
γ	Grade angle
\mathbf{g}	Control coefficient vector
g	Gravitational constant
T^*	Preview time window
$f(t+T^*)$	Previewed path input T^* seconds ahead
U	Forward vehicle velocity
\mathbf{m}^T	Constant observer vector; provides vehicle lateral position
F_r	Rolling resistance
a_r	Static rolling and driveline resistance
b_r	Linear rolling and driveline resistance
c_r	Aerodynamic rolling and driveline resistance

Optimization

The single-point model implemented by the block finds the steering command that minimizes a local performance index, J , over the current preview interval, $(t, t+T)$.

$$J = \frac{1}{T} \int_t^{t+T} [f(\eta) - y(\eta)]^2 d\eta$$

To minimize J with respect to the steering command, this condition must be met.

$$\frac{dJ}{du} = 0$$

You can express the optimal control solution in terms of a current non-optimal and corresponding nonzero preview output error T^* seconds ahead^{1, 2, 3}.

$$u^o(t) = u(t) + \frac{e(t + T^*)}{a^*}$$

The block uses the preview distance and vehicle longitudinal velocity to determine the preview time window.

$$T^* = \frac{L}{U}$$

The equations use these variables.

T^*	Preview time window
$f(t+T^*)$	Previewed path input T^* sec ahead
$y(t+T^*)$	Previewed plant output T^* sec ahead
$e(t+T^*)$	Previewed error signal T^* sec ahead
$u(t), u^o(t)$	Steer angle and optimal steer angle, respectively
L	Preview distance
J	Performance index
U	Forward (longitudinal) vehicle velocity

Driver Lag

The single-point model implemented by the block introduces a driver lag. The driver lag accounts for the delay when the driver is tracking tasks. Specifically, it is the transport delay deriving from perceptual and neuromuscular mechanisms. To calculate the driver transport delay, the block implements this equation.

$$H(s) = e^{-s\tau}$$

The equations use these variables.

τ	Driver transport delay
$y(t+T^*)$	Previewed plant output T^* sec ahead
$e(t+T^*)$	Previewed error signal T^* sec ahead
$u(t), u^o(t)$	Steer angle and optimal steer angle, respectively
J	Performance index

Ports

Input

VelRef — Reference vehicle velocity

scalar

Reference velocity, v_{ref} , in m/s.

EnbAccelOvr — Enable acceleration command override

scalar

Enable acceleration command override.

Dependencies

To enable this port, select **Acceleration override**.

Data Types: Boolean

AccelOvrCmd — Acceleration override command

scalar

Acceleration override command, normalized from 0 through 1.

Dependencies

To enable this port, select **Acceleration override**.

Data Types: double

AccelHld — Acceleration hold

scalar

Boolean signal that holds the acceleration command at the current value.

Dependencies

To enable this port, select **Acceleration hold**.

Data Types: Boolean

AccelZero — Disable acceleration command

scalar

Disable acceleration command.

Dependencies

To enable this port, select **Acceleration disable**.

Data Types: Boolean

EnbDecelOvr — Enable deceleration command override

scalar

Enable deceleration command override.

Dependencies

To enable this port, select **Deceleration override**.

Data Types: Boolean

DecelOvrCmd — Deceleration override command

scalar

Deceleration override command, normalized from 0 through 1.

Dependencies

To enable this port, select **Deceleration override**.

Data Types: double

DecelHld — Deceleration hold

scalar

Boolean signal that holds the deceleration command at the current value.

Dependencies

To enable this port, select **Deceleration hold**.

Data Types: Boolean

DecelZero — Disable deceleration command

scalar

Disable deceleration command.

Dependencies

To enable this port, select **Deceleration disable**.

Data Types: Boolean

ExtGear — Gear

scalar

Gear	Integer
Park	80
Reverse	-1
Neutral	0
Drive	1
Gear	Gear number

Dependencies

To enable this port, set **Shift type, shiftType** to External.

VelFdbk — Longitudinal vehicle velocity

scalar

Longitudinal vehicle velocity, U , in the vehicle-fixed frame, in m/s.

Grade — Road grade angle

scalar

Road grade angle, θ or γ , in deg.

Output**Info — Bus signal**

bus

Bus signal containing these block calculations.

Signal	Variable	Description
Accel	y_{acc}	Commanded vehicle acceleration, normalized from 0 through 1
Decel	y_{dec}	Commanded vehicle deceleration, normalized from 0 through 1
Gear		Integer value of commanded gear
Clutch		Clutch command
Err	e_{ref}	Difference in reference vehicle speed and vehicle speed
ErrSqrSum	$\int_0^t e_{ref}^2 dt$	Integrated square of error
ErrMax	$\max(e_{ref}(t))$	Maximum error during simulation
ErrMin	$\min(e_{ref}(t))$	Minimum error during simulation
ExtActions	EnblAccelOvr	Override the accelerator command with an input acceleration command
	AccelOvrCmd	Input accelerator override command
	AccelHld	Hold the acceleration command at the current value
	AccelZero	Disable the acceleration command
	EnblDecelOvr	Override the decelerator command with an input deceleration command
	DecelOvrCmd	Input deceleration override command
	DecelHld	Hold the decelerator command at current value
	DecelZero	Disable the decelerator command

AccelCmd — Commanded vehicle acceleration

scalar

Commanded vehicle acceleration, y_{acc} , normalized from 0 through 1.

DecelCmd — Commanded vehicle deceleration

scalar

Commanded vehicle deceleration, y_{dec} , normalized from 0 through 1.

GearCmd — Commanded vehicle gear

scalar

Integer value of commanded vehicle gear.

Gear	Integer
Park	80
Reverse	-1

Gear	Integer
Neutral	0
Drive	1
Gear	Gear number

Dependencies

To enable this port, select **Output gear signal**.

Parameters

External Actions

Accelerator override – Override acceleration command

off (default) | on

Select to override the acceleration command with an input acceleration command.

Dependencies

Selecting this parameter creates the EnblAccelOvr and AccelOvrCmd input ports.

Accelerator hold – Hold acceleration command

off (default) | on

Select to hold the acceleration command.

Dependencies

Selecting this parameter creates the AccelHld input port.

Accelerator disable – Disable acceleration command

off (default) | on

Select to disable the acceleration command.

Dependencies

Selecting this parameter creates the AccelZero input port.

Decelerator override – Override deceleration command

off (default) | on

Select to override the deceleration command with an input deceleration command.

Dependencies

Selecting this parameter creates the EnblDecelOvr and DecelOvrCmd input ports.

Decelerator hold – Hold deceleration command

off (default) | on

Select to hold the deceleration command.

Dependencies

Selecting this parameter creates the DecelHld input port.

Decelerator disable – Disable deceleration command

off (default) | on

Select to disable the deceleration command.

Dependencies

Selecting this parameter creates the DecelZero input port.

Configuration**Control type, cntrlType – Longitudinal control**

PI (default) | Scheduled PI | Predictive

Type of longitudinal control.

Setting	Block Implementation
PI	Proportional-integral (PI) control with tracking windup and feed-forward gains.
Scheduled PI	PI control with tracking windup and feed-forward gains that are a function of vehicle velocity.
Predictive	<p>Optimal single-point preview (look ahead) control model developed by C. C. MacAdam^{1, 2, 3}. The model represents driver steering control behavior during path-following and obstacle avoidance maneuvers. Drivers preview (look ahead) to follow a predefined path. To implement the MacAdam model, the block:</p> <ul style="list-style-type: none"> • Represents the dynamics as a linear single track (bicycle) vehicle • Minimizes the previewed error signal at a single point T^* seconds ahead in time • Accounts for the driver lag deriving from perceptual and neuromuscular mechanisms

Shift type, shftType – Shift type

None (default) | Reverse, Neutral, Drive | Scheduled | External

Shift type.

Setting	Block Implementation
None	<p>No transmission. Block outputs a constant gear of 1.</p> <p>Use this setting to minimize the number of parameters you need to generate acceleration and braking commands to track forward vehicle motion. This setting does not allow reverse vehicle motion.</p>

Setting	Block Implementation
Reverse, Neutral, Drive	<p>Block uses a Stateflow chart to model reverse, neutral, and drive gear shift scheduling.</p> <p>Use this setting to generate acceleration and braking commands to track forward and reverse vehicle motion using simple reverse, neutral, and drive gear shift scheduling. Depending on the vehicle state and vehicle velocity feedback, the block uses the initial gear and time required to shift to shift the vehicle up into drive or down into reverse or neutral.</p> <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>
Scheduled	<p>Block uses a Stateflow chart to model reverse, neutral, park, and N-speed gear shift scheduling.</p> <p>Use this setting to generate acceleration and braking commands to track forward and reverse vehicle motion using reverse, neutral, park, and N-speed gear shift scheduling. Depending on the vehicle state and vehicle velocity feedback, the block uses these parameters to determine the:</p> <ul style="list-style-type: none"> • Initial gear • Upshift and downshift accelerator pedal positions • Upshift and downshift velocity • Timing for shifting and engaging forward and reverse from neutral <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>
External	<p>Block uses the input gear, vehicle state, and velocity feedback to generate acceleration and braking commands to track forward and reverse vehicle motion.</p> <p>For neutral gears, the block uses braking commands to control the vehicle speed. For reverse gears, the block uses an acceleration command to generate torque and a brake command to reduce vehicle speed.</p>

Reference and feedback units, velUnits – Velocity units

m/s (default)

Vehicle velocity reference and feedback units.

Dependencies

If you set **Control type, cntrlType** control type to Scheduled or Scheduled PI, the block uses the **Reference and feedback units, velUnits** for the **Nominal speed, vnom** parameter dimension.

If you set **Shift Type, shftType** to Scheduled, the block uses the **Longitudinal velocity units, velUnits** for these parameter dimensions:

- **Upshift velocity data table, upShftTbl**

- **Downshift velocity data table, `dwnShftTbl`**

Output gear signal – Create GearCmd output port

off (default) | on

Specify to create output port GearCmd.

Control

Longitudinal

Proportional gain, K_p – Gain

10 (default) | scalar

Proportional gain, K_p , dimensionless.

Dependencies

To create this parameter, set **Control type** to PI.

Integral gain, K_i – Gain

5 (default) | scalar

Proportional gain, K_i , dimensionless.

Dependencies

To create this parameter, set **Control type** to PI.

Velocity feed-forward, K_{ff} – Gain

.1 (default) | scalar

Velocity feed-forward gain, K_{ff} , dimensionless.

Dependencies

To create this parameter, set **Control type** to PI.

Grade angle feed-forward, K_g – Gain

0 (default) | scalar

Grade angle feed-forward gain, K_g , in 1/deg.

Dependencies

To create this parameter, set **Control type** to PI.

Velocity gain breakpoints, `VehVelVec` – Breakpoints

[0 100] (default) | vector

Velocity gain breakpoints, `VehVelVec`, dimensionless.

Dependencies

To create this parameter, set **Control type** to Scheduled PI.

Velocity feed-forward gain values, `KffVec` – Gain

[.1 .1] (default) | vector

Velocity feed-forward gain values, K_{ffVec} , as a function of vehicle velocity, dimensionless.

Dependencies

To create this parameter, set **Control type** to Scheduled PI.

Proportional gain values, K_pVec – Gain

[10 10] (default) | vector

Proportional gain values, K_pVec , as a function of vehicle velocity, dimensionless.

Dependencies

To create this parameter, set **Control type** to Scheduled PI.

Integral gain values, K_iVec – Gain

[5 5] (default) | vector

Integral gain values, K_iVec , as a function of vehicle velocity, dimensionless.

Dependencies

To create this parameter, set **Control type** to Scheduled PI.

Grade angle feed-forward values, K_gVec – Grade gain

[0 0] (default) | vector

Grade angle feed-forward values, K_gVec , as a function of vehicle velocity, in 1/deg.

Dependencies

To create this parameter, set **Control type** to Scheduled PI.

Nominal speed, v_{nom} – Nominal vehicle speed

5 (default) | scalar

Nominal vehicle speed, v_{nom} , in units specified by the **Reference and feedback units, velUnits** parameter. The block uses the nominal speed to normalize the controller gains.

Dependencies

To create this parameter, set **Control type** to PI or Scheduled PI.

Anti-windup, K_{aw} – Gain

1 (default) | scalar

Anti-windup gain, K_{aw} , dimensionless.

Dependencies

To create this parameter, set **Control type** to PI or Scheduled PI.

Error filter time constant, τ_{err} – Filter

.01 (default) | scalar

Error filter time constant, τ_{err} , in s. To disable the filter, enter 0.

Dependencies

To create this parameter, set **Control type** to PI or Scheduled PI.

Predictive**Vehicle mass, m – Mass**

1500 (default) | scalar

Vehicle mass, m , in kg.

Dependencies

To create this parameter, set **Longitudinal control type, `ctrlType`** to Predictive.

Effective vehicle total tractive force, K_{pt} – Tractive force

3000 (default) | scalar

Effective vehicle total tractive force, K_{pt} , in N.

Dependencies

To create this parameter, set **Longitudinal control type, `ctrlType`** to Predictive.

Driver response time, τ – Tau

.1 (default) | scalar

Driver response time, τ , in s.

Dependencies

To create this parameter, set **Longitudinal control type, `ctrlType`** to Predictive.

Preview distance, L – Distance

2 (default) | scalar

Driver preview distance, L , in m.

Dependencies

To create this parameter, set **Longitudinal control type, `ctrlType`** to Predictive.

Rolling resistance coefficient, a_R – Resistance

200 (default) | scalar

Static rolling and driveline resistance coefficient, a_R , in N. Block uses the parameter to estimate the constant acceleration or braking effort.

Dependencies

To create this parameter, set **Longitudinal control type, `ctrlType`** to Predictive.

Rolling and driveline resistance coefficient, b_R – Resistance

2.5 (default) | scalar

Rolling and driveline resistance coefficient, b_R , in N·s/m. Block uses the parameter to estimate the linear velocity-dependent acceleration or braking effort.

Dependencies

To create this parameter, set **Longitudinal control type, `cntrlType`** to Predictive.

Aerodynamic drag coefficient, `cR` – Drag

.5 (default) | scalar

Aerodynamic drag coefficient, c_R , in $N \cdot s^2/m^2$. Block uses the parameter to estimate the quadratic velocity-dependent acceleration or braking effort.

Dependencies

To create this parameter, set **Longitudinal control type, `cntrlType`** to Predictive.

Gravitational constant, `g` – Gravitational constant

9.81 (default) | scalar

Gravitational constant, g , in m/s^2 .

Dependencies

To create this parameter, set **Longitudinal control type, `cntrlType`** to Predictive.

Shift**Reverse, Neutral, Drive****Initial gear, `GearInit` – Initial gear**

0 (default) | scalar

Integer value of the initial gear. The block uses the initial gear to generate acceleration and braking commands to track forward and reverse vehicle motion.

Gear	Integer
Park	80
Reverse	-1
Neutral	0
Drive	1
Gear	Gear number

Dependencies

To create this parameter, set **Shift type, `shftType`** to Reverse, Neutral, Drive or Scheduled. If you specify Reverse, Neutral, Drive, the **Initial Gear, `GearInit`** parameter value can be only -1, 0, or 1.

Time required to shift, `tShift` – Time

.1 (default) | scalar

Time required to shift, t_{Shift} , in s. The block uses the time required to shift to generate acceleration and braking commands to track forward and reverse vehicle motion using reverse, neutral, and drive gear shift scheduling.

Dependencies

To create this parameter, set **Shift type, shftType** to Reverse, Neutral, Drive.

Scheduled**Initial gear, GearInit – Initial gear**

0 (default) | scalar

Integer value of the initial gear. The block uses the initial gear to generate acceleration and braking commands to track forward and reverse vehicle motion.

Gear	Integer
Park	80
Reverse	-1
Neutral	0
Drive	1
Gear	Gear number

Dependencies

To create this parameter, set **Shift type, shftType** to Reverse, Neutral, Drive or Scheduled. If you specify Reverse, Neutral, Drive, the **Initial Gear, GearInit** parameter value can be only -1, 0, or 1.

Up and down shift accelerator pedal positions, pdlVec – Pedal position breakpoints

[0.1 0.4 0.5 0.9] (default) | [1-by-m] vector

Pedal position breakpoints for lookup tables when calculating upshift and downshift velocities, dimensionless. Vector dimensions are 1 by the number of pedal position breakpoints, m.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Upshift velocity data table, upShftTbl – Table

[m-by-n] array

Upshift velocity data as a function of pedal position and gear, in units specified by the **Reference and feedback units, velUnits** parameter. Upshift velocities indicate the vehicle velocity at which the gear should increase by 1.

The array dimensions are m pedal positions by n gears. The first column of data, when n equals 1, is the upshift velocity for the neutral gear.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Downshift velocity data table, dwnShftTbl – Table

[m-by-n] array

Downshift velocity data as a function of pedal position and gear, in units specified by the **Reference and feedback units, velUnits** parameter. Downshift velocities indicate the vehicle velocity at which the gear should decrease by 1.

The array dimensions are m pedal positions by n gears. The first column of data, when n equals 1, is the downshift velocity for the neutral gear.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Time required to shift, tClutch – Time

.5 (default) | scalar

Time required to shift, t_{Clutch} , in s.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Time required to engage reverse from neutral, tRev – Time

.5 (default) | scalar

Time required to engage reverse from neutral, t_{Rev} , in s.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Time required to engage park from neutral, tPark – Time

120 (default) | scalar

Time required to engage park from neutral, t_{Park} , in s.

Dependencies

To create this parameter, set **Shift type, shftType** to Scheduled.

Version History

Introduced in R2017a

References

- [1] MacAdam, C. C. "An Optimal Preview Control for Linear Systems". *Journal of Dynamic Systems, Measurement, and Control*. Vol. 102, Number 3, Sept. 1980.
- [2] MacAdam, C. C. "Application of an Optimal Preview Control for Simulation of Closed-Loop Automobile Driving ". *IEEE Transactions on Systems, Man, and Cybernetics*. Vol. 11, Issue 6, June 1981.
- [3] MacAdam, C. C. *Development of Driver/Vehicle Steering Interaction Models for Dynamic Analysis*. Final Technical Report UMTRI-88-53. Ann Arbor, Michigan: The University of Michigan Transportation Research Institute, Dec. 1988.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

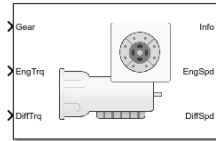
Drive Cycle Source | Vehicle Body Total Road Load

Transmission Blocks

Automated Manual Transmission

Ideal automated manual transmission

Library: Powertrain Blockset / Transmission / Transmission Systems



Description

The Automated Manual Transmission block implements an ideal automated transmission (AMT). An AMT is a manual transmission with additional actuators and an electronic control unit (ECU) to regulate clutch and gear selection based on commands from a controller. The number of gears is specified via an integer vector with corresponding gear ratios, inertias, viscous damping, and efficiency factors. The clutch and synchronization engagement rates are linear and adjustable.

Use the block for:

- Power and torque capacity sizing
- Determining gear ratio impact on fuel economy and performance

To determine the rotational drive shaft speed and reaction torque, the Automated Manual Transmission block calculates:

- Clutch lock-up and clutch friction
- Locked rotational dynamics
- Unlocked rotational dynamics

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

Clutch Control

The AMT delivers drive shaft torque continuously by controlling the pressure signals from the clutch. If you select **Control type** parameter *Ideal integrated controller*, the block generates idealized clutch pressure signals. To use your own clutch control signals, select **Control type** parameter *External control*.

Clutch Lock-Up and Clutch Friction

Based on the clutch lock-up condition, the block implements one of these friction models.

If	Clutch Condition	Friction Model
$\omega_i \neq N\omega_d$ or $T_S < T_f - Nw_i b_i $	Unlocked	$T_f = T_k$ where, $T_k = F_c R_{eff} \mu_k \tanh\left[4\left(\frac{\omega_i}{N} - \omega_d\right)\right]$ $T_s = F_c R_{eff} \mu_s$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$
$\omega_i = N\omega_t$ and $T_S \geq T_f - Nb_i \omega_i $	Locked	$T_f = T_s$

The equations use these variables.

ω_t	Output drive shaft speed
ω_i	Input drive shaft speed
ω_d	Drive shaft speed
b_i	Viscous damping
F_c	Applied clutch force
N	Engaged gear
T_f	Frictional torque
T_k	Kinetic frictional torque
T_s	Static frictional torque
R_{eff}	Effective clutch radius
R_o	Annular disk outer radius
R_i	Annular disk inner radius
μ_s	Coefficient of static friction
μ_k	Coefficient of kinetic friction

Locked Rotational Dynamics

To model the rotational dynamics when the clutch is locked, the block implements these equations.

$$\dot{\omega}_d J_N = \eta_N T_d - \frac{\omega_i}{N} b_N + N T_i$$

$$\omega_i = N \omega_d$$

The block determines the input torque, T_i , through differentiation.

The equations use these variables.

ω_i	Input drive shaft speed
ω_d	Drive shaft speed
N	Engaged gear
b_N	Engaged gear viscous damping
J_N	Engaged gear inertia
η_N	Engaged gear efficiency
T_d	Drive shaft torque
T_i	Applied input torque

Unlocked Rotational Dynamics

To model the rotational dynamics when the clutch is unlocked, the block implements this equation.

$$\dot{\omega}_d J_N = N T_i - \omega_d b_N + T_d$$

where:

ω_d	Drive shaft speed
N	Engaged gear
b_N	Engaged gear viscous damping
J_N	Engaged gear inertia
T_d	Drive shaft torque
T_i	Applied input torque

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrEng	Engine power	P_{eng}	$\omega_i T_i$
		PwrDiffrntl	Differential power	P_{diff}	$\omega_d T_d$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrEffLoss	Mechanical power loss	$P_{effloss}$	$\omega_d T_d (\eta_N - 1)$
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	$-b_N \omega_d^2 - b_{in} \omega_i^2$
		PwrClutchLoss	Clutch power loss	P_{mech}	When locked: 0 When unlocked: $-T_k(\omega_i - N\omega_d)$

Bus Signal		Description	Variable	Equations
PwrStored	— Stored energy rate of change <ul style="list-style-type: none"> • Positive signals indicate an increase • Negative signals indicate a decrease 	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str} When locked: $\dot{\omega}_i \omega_i (J_{in} + \frac{J_N}{N^2})$ When unlocked: $J_{in} \dot{\omega}_i \omega_i + J_N \dot{\omega}_d \omega_d$

The equations use these variables.

b_N	Engaged gear viscous damping
J_N	Engaged gear rotational inertia
J_{in}	Flywheel rotational inertia
η_N	Engaged gear efficiency
N	Engaged gear ratio
T_i	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper
T_d	Applied load torque, typically from the differential or drive shaft
ω_d	Initial input drive shaft rotational velocity
$\omega_i, \dot{\omega}_i$	Applied drive shaft angular speed and acceleration

Ports

Input

Gear — Gear number to engage

scalar

Integer value of gear number to engage.

ClutchCmd — Clutch command

scalar

Clutch pressure command.

Dependencies

To create this port, select **Control type** parameter External control.

EngTrq — Applied input torque

scalar

Applied input torque, T_i , typically from the engine crankshaft or dual mass flywheel damper, in N·m.

DiffTrq — Applied load torque

scalar

Applied load torque, T_d , typically from the differential or driveshaft, in N·m.

Temp – Oil temperature

scalar

Oil temperature, in K. To determine the efficiency, the block uses a 4D lookup table that is a function of:

- Gear
- Input torque
- Input speed
- Oil temperature

Dependencies

To create this port, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Output

Info – Bus signal

bus

Bus signal contains these block calculations.

Signal		Description	Variable	Units	
Eng	EngTrq	Input applied torque	T_i	N·m	
	EngSpd	Input drive shaft speed	ω_i	rad/s	
Diff	DiffTrq	Output drive shaft torque	T_t	N·m	
	DiffSpd	Output drive shaft speed	ω_t	rad/s	
Cltch	CltchForce	Applied clutch force	F_c	N	
	CltchLocked	Clutch lock status, Boolean: • Locked – 0 • Unlocked – 1	N/A	N/A	
Trans	TransSpdRatio	Speed ratio at time t	$\phi(t)$	N/A	
	TransEta	Ratio of output power to input power	η	N/A	
	TransGearCmd	Commanded gear	N_{cmd}	N/A	
	TransGear	Engaged gear	N	N/A	
PwrInfo	PwrTrnsfrd	PwrEng	Engine power	P_{eng}	W
		PwrDiffrentl	Differential power	P_{diff}	W
	PwrNotTrnsfrd	PwrEffLoss	Mechanical power loss	$P_{effloss}$	W

Signal		Description	Variable	Units	
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	W
		PwrClutchLoss	Clutch power loss	P_{mech}	W
	PwrStored	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str}	W

EngSpd – Angular speed

scalar

Applied drive shaft angular speed input, ω_i , in rad/s.**DiffSpd – Angular speed**

scalar

Drive shaft angular speed output, ω_d , in rad/s.**Parameters****Control type – Specify control type**

Ideal integrated controller (default) | External control

The AMT delivers drive shaft torque continuously by controlling the pressure signals from the clutch. If you select **Control type** parameter `Ideal integrated controller`, the block generates idealized clutch pressure signals. To use your own clutch control signals, select **Control type** parameter `External control`.

Dependencies

This table summarizes the port configurations.

Control Mode	Creates Ports
External control	ClutchCmd

Efficiency factors – Specify efficiency calculation

Gear only (default) | Gear, input torque, input speed, and temperature

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

Dependencies

Setting Parameter To	Enables
Gear only	Efficiency vector, eta
Gear, input torque, input speed, and temperature	Efficiency torque breakpoints, Trq_bpts Efficiency speed breakpoints, omega_bpts Efficiency temperature breakpoints, Temp_bpts Efficiency lookup table, eta_tbl

Transmission

Input shaft inertia, Jin – Inertia

.01 (default) | scalar

Input shaft inertia, in kg·m².

Input shaft damping, bin – Damping

.001 (default) | scalar

Input shaft damping, in N·m·s/rad.

Initial input velocity, omegain_o – Angular velocity

0 (default) | scalar

Angular velocity, in rad/s.

Gear number vector, G – Specify number of transmission speeds

[-1, 0, 1, 2, 3, 4, 5] (default) | vector

Vector of integer gear commands used to specify the number of transmission speeds. Neutral gear is 0. For example, you can set these parameter values.

To Specify	Set Gear number, G To
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]
Three transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3]
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Transmission damping vector**, and **Efficiency vector** parameters must be equal.

Efficiency torque breakpoints, Trq_bpts – Breakpoints

[25, 50, 75, 100, 150, 200, 250] (default) | vector

Torque breakpoints for efficiency table, in N·m.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency speed breakpoints, omega_bpts – Breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | vector

Speed breakpoints for efficiency table, rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency temperature breakpoints, Temp_bpts – Breakpoints

[313 358] (default) | vector

Temperature breakpoints for efficiency table, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Gear ratio vector, N – Ratio of input speed to output speed

[-4.47, 1, 4.47, 2.47, 1.47, 1, 0.8] (default) | vector

Vector of gear ratios (that is, input speed to output speed) with indices corresponding to the ratios specified in **Gear number, G**. For neutral, set the gear ratio to 1. For example, you can set these parameter values.

To Specify Gear Ratios For	Set Gear number, G To	Set Gear ratio, N To
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]	[1, 4.47, 2.47, 1.47, 1]
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]	[-4.47, 1, 4.47, 2.47, 1.47, 1, 0.8]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Transmission damping vector**, and **Efficiency vector** parameters must be equal.

Transmission inertia vector, Jout – Gear rotational inertia

[0.128 0.01 0.128 0.1 0.062 0.028 0.01] (default) | vector

Vector of gear rotational inertias, with indices corresponding to the inertias specified in **Gear number, G**, in kg·m². For example, you can set these parameter values.

To Specify Inertia For	Set Gear number, G To	Set Inertia, J To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.01, 2.28, 2.04, 0.32, 0.028]
Inertia for five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[2.28, 0.01, 2.28, 2.04, 0.32, 0.028, 0.01]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Transmission damping vector**, and **Efficiency vector** parameters must be equal.

Transmission damping vector, b_{out} – Gear viscous damping coefficient

[0.003 0.001 0.003 0.0025 0.002 0.001 0.001] (default) | vector

Vector of gear viscous damping coefficients, with indices corresponding to the coefficients specified in **Gear number, G** , in N·m·s/rad. For example, you can set these parameter values.

To Specify Damping For	Set Gear number, G To	Set Damping, b To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.001, 0.003, 0.0025, 0.002, 0.001]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.003, 0.001, 0.003, 0.0025, 0.002, 0.001, 0.001]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Transmission damping vector**, and **Efficiency vector** parameters must be equal.

Efficiency vector, η_a – Gear efficiency

[0.9, 0.9, 0.9, 0.9, 0.9, 0.95, 0.95] (default) | vector

Vector of gear mechanical efficiency, with indices corresponding to the efficiencies specified in **Gear number, G** . For example, you can set these parameter values.

To Specify Efficiency For	Set Gear number, G To	Set Efficiency, η_a To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.9, 0.9, 0.9, 0.9, 0.95]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.9, 0.9, 0.9, 0.9, 0.9, 0.95, 0.95]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Transmission damping vector**, and **Efficiency vector** parameters must be equal.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear only.

Efficiency lookup table, η_{tbl} – Gear efficiency

array

Table of gear mechanical efficiency, η_N as a function of gear, input torque, input speed, and temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Initial output velocity, ω_{out_o} – Transmission

0 (default) | scalar

Transmission initial output rotational velocity, ω_{to} , in rad/s. If you select **Clutch initially locked**, the block ignores the **Initial output velocity, ω_{out_o}** parameter value.

Initial gear, G_o – Engaged gear

0 (default) | scalar

Initial gear to engage, G_o .

Clutch and Synchronizer**Clutch pressure time constant, tauc – Time**

.02 (default) | scalar

Pressure input filter time constant, τ_c , in s.**Synchronization time, ts – Time**

.25 (default) | scalar

Time required for gear selection and synchronization, t_s , in s.**Clutch time, tc – Time**

.5 (default) | scalar

Time required to engage and disengage the clutch during shift events, t_c , in s.**Dependencies**To create this parameter, select **Control type** parameter Ideal integrated controller.**Effective clutch radius, R – Radius**

.2 (default) | scalar

The effective radius, R_{eff} , used with the applied clutch friction force to determine the friction force, in m. The effective radius is defined as:

$$R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$$

The equation uses these variables.

 R_o Annular disk outer radius R_i Annular disk inner radius**Clutch force gain, K_c – Force**

5e3 (default) | scalar

Open loop lock-up clutch gain, K_c , in N.**Clutch static friction coefficient, mus – Coefficient**

0.6 (default) | scalar

Dimensionless clutch disc coefficient of static friction, μ_s .**Clutch kinematic friction coefficient, muk – Coefficient**

0.4 (default) | scalar

Dimensionless clutch disc coefficient of kinetic friction, μ_k .**Clutch initially locked – Select to initially lock clutch**

off (default) | on

Select to lock clutch initially.

Dependencies

To create this parameter, select **Control type** parameter Ideal integrated controller.

Synchronizer initially locked – Select to initially lock synchronizer

off (default) | on

Select to initially lock synchronizer.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

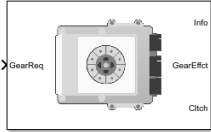
See Also

AMT Controller | Dual Clutch Transmission | Continuously Variable Transmission | Ideal Fixed Gear Transmission

AMT Controller

Automated manual transmission controller with clutch open, close, and synchronization timing

Library: Powertrain Blockset / Transmission / Transmission Controllers



Description

The AMT Controller block implements an automated manual transmission (AMT) controller. You can specify the clutch open, close, and synchronization timing parameters. The block determines the clutch commands using integrator-based timers and latching logic that is based on the specified timing parameters and gear request.

Ports

Inputs

GearReq — Gear number to engage

scalar

Gear number request, G_{req} .

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable
GearReq	Gear number request	G_{req}
GearEngd	Nominal gear commanded by the controller	G_o
Clutch	Clutch pressure command for gears, between 0 and 1	NA

GearEffct — Effective gear for shifting

scalar

Effective gear for shifting. The block uses this signal for the smooth application of inertial, efficiency, gear ratio, and damping parameters.

Clutch — Command for clutch pressure

scalar

Clutch pressure command, between 0 and 1.

Parameters

Initial gear, G_o — Engaged gear

0 (default) | scalar

Initial gear to engage, G_o .

Clutch actuation time, t_c — Time

.1 (default) | scalar

Time required to engage and disengage the clutch during shift events, t_c , in s.

Synchronizer time, t_s — Time

.01 (default) | scalar

Time required for gear selection and synchronization, t_s , in s.

Sample period, dt — Time

-1 (default) | scalar

Sample period, dt , in s.

Clutch initially locked — Select to initially lock clutch

off (default) | on

Selecting this parameter initially locks the clutch.

Synchronizer initially locked — Select to initially lock synchronizer

off (default) | on

Selecting this parameter initially locks the synchronizer.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

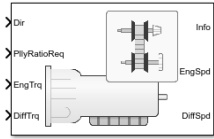
See Also

Automated Manual Transmission

Continuously Variable Transmission

Push belt continuously variable transmission with independent radii control

Library: Powertrain Blockset / Transmission / Transmission Systems



Description

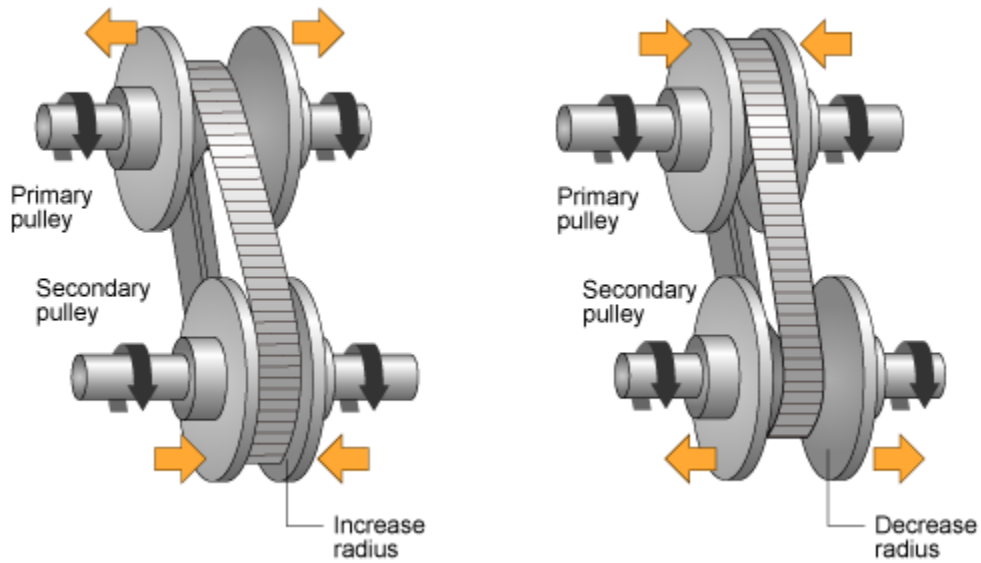
The Continuously Variable Transmission block implements a push belt continuously variable transmission (CVT) with independent radii control. Use the block for control system design, powertrain matching, and fuel economy studies. You can configure the block for internal or external control:

- Internal — Input direction and pulley ratio requests
- External — Input direction and pulley displacement requests

The table summarizes the pulley kinematic, speed reduction, and dynamic calculations made by the Continuously Variable Transmission block.

Calculation	Pulley Kinematics	Reverse and Final Speed Reduction	Dynamics
Final angular speed ratio	✓	✓	✓
Belt torque applied to the secondary and primary pulleys			✓
Torque applied to the secondary and primary pulleys		✓	
Angular velocity of secondary and primary pulleys	✓	✓	✓
Belt and pulley geometry	✓		
Belt linear speed			✓
Wrap angle on secondary and primary pulley	✓		
Primary and secondary pulley radii	✓		

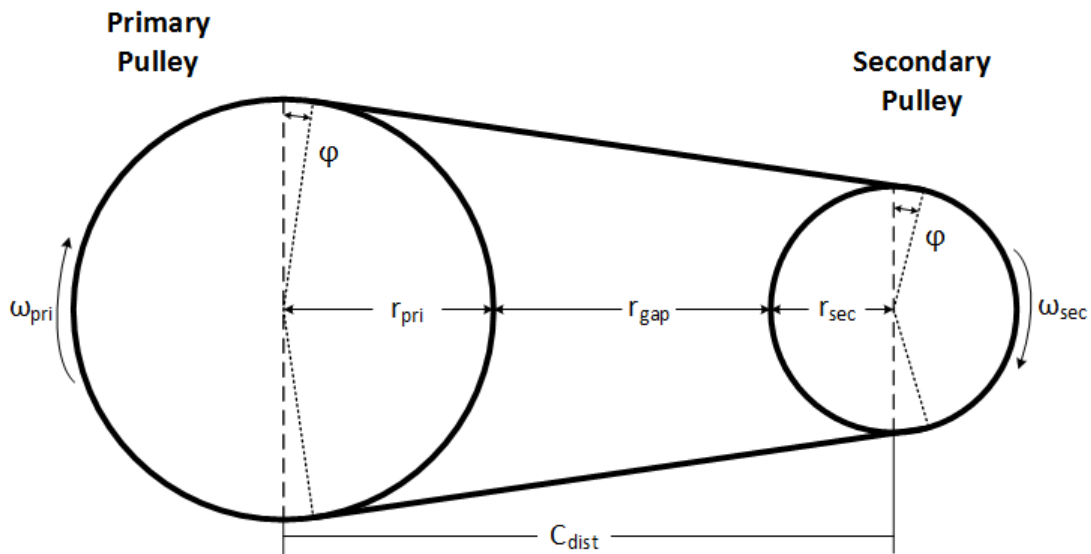
The figure shows the CVT variator with two configurations. In the first configuration, which illustrates speed reduction, the variator is set to decrease the primary pulley radius and increase the secondary pulley radius. In the second configuration, which illustrates overdrive, the variator is set to increase the primary pulley radius and decrease the secondary pulley radius.



Pulley Kinematics

Using the physical dimensions of the system, the block calculates the primary and secondary variator positions that meet the pulley ratio request.

The figure and equations summarize the geometric dependencies.



$$\begin{aligned}
C_{dist} &= r_{p_{max}} + r_{gap} + r_{sec_max} \\
L_0 &= f(r_{p_{max}}, r_{s_{max}}, r_{p_{min}}, r_{s_{min}}, C_{dist}) \\
ratio_{command} &= f(ratio_{request}, ratio_{max}, ratio_{min}) \\
r_{pri} &= f(r_0, ratio_{command}, C_{dist}) \\
r_{sec} &= f(r_0, ratio_{command}, C_{dist}) \\
x_{pri} &= f(r_0, r_{pri}, \theta_{wedge}) \\
x_{sec} &= f(r_0, r_{sec}, \theta_{wedge})
\end{aligned}$$

The equations use these variables.

$ratio_{request}$	Pulley gear ratio request
$ratio_{command}$	Pulley gear ratio command, based on request and physical limitations
r_{gap}	Gap distance between variator pulleys
C_{dist}	Distance between variator pulley centers
$r_{p_{max}}$	Maximum variator primary pulley radius
$r_{s_{max}}$	Maximum variator secondary pulley radius
$r_{p_{min}}$	Minimum variator primary pulley radius
$r_{s_{min}}$	Minimum variator secondary pulley radius
r_0	Initial pulley radii with gear ratio of 1
L_0	Initial belt length, resulting from variator specification
x_{pri}	Variator primary pulley displacement, resulting from controller request
x_{sec}	Variator secondary pulley displacement, resulting from controller request
r_{pri}	Variator primary pulley radius, resulting from controller request
r_{sec}	Variator secondary pulley radius, resulting from controller request
θ_{wedge}	Variator wedge angle
Φ	Angle of belt to pulley contact point
L	Belt length, resulting from variator position

Reverse and Final Speed Reduction

The CVT input shaft connects to a planetary gear set that drives the primary pulley. The shift direction determines the input gear inertia, efficiency, and gear ratio. The shift direction is the filtered commanded direction:

$$\frac{Dir_{shift}(s)}{Dir} = \frac{1}{\tau_{sS} + 1}$$

For forward motion ($Dir_{shift} = 1$):

$$\begin{aligned}
N_i &= 1 \\
\eta_i &= \eta_{fwd} \\
J_i &= J_{fwd}
\end{aligned}$$

For reverse motion ($Dir_{shift} = -1$):

$$N_i = -N_{rev}$$

$$\eta_i = \eta_{rev}$$

$$J_i = J_{rev}$$

The gear ratio and efficiency determine the input drive shaft speed and torque applied to the primary pulley:

$$T_{app_pri} = \eta_i N_i T_i$$

The block reduces the secondary pulley speed and applied torque using a fixed gear ratio.

$$T_{app_sec} = \frac{T_o}{\eta_o N_o}$$

$$\omega_o = \frac{\omega_{sec}}{N_o}$$

The final gear ratio, without slip, is given by:

$$N_{final} = \frac{\omega_i}{\omega_o} = N_i N_o \frac{r_{sec}}{r_{pri}}$$

The equations use these variables.

N_i	Input planetary gear ratio
Dir	CVT direction command
Dir_{shift}	Direction used to determine planetary inertia, efficiency, and ratio
τ_s	Direction shift time constant
η_{fwd}, η_{rev}	Forward and reverse gear efficiency, respectively
J_{fwd}, J_{rev}	Forward and reverse gear inertia, respectively
N_{rev}	Reverse gear ratio
T_{app_pri}, T_{app_sec}	Torque applied to primary and secondary pulleys, respectively
T_i	Input drive shaft torque
ω_i, ω_o	Input and output drive shaft speed, respectively
$\omega_{pri}, \omega_{sec}$	Primary and secondary pulley speed, respectively
N_{final}	Total no-slip gear ratio

Dynamics

The maximum torque that the CVT can transmit depends on the friction between the pulleys and belt. According to *Prediction of Friction Drive Limit of Metal V-Belt*, the torque friction is defined as:

$$T_{fric}(r_p, \mu) = \frac{2\mu F_{ax} r_p}{\cos(\theta_{wedge})}$$

Without macro slip, the tangential acceleration of the pulley is assumed to be equal to the belt acceleration. Once the torque reaches the static friction limit, the belt begins to slip, and the pulley and belt acceleration are independent. During slip, the torque transmitted by the belt is a function of the kinetic friction factor. During the transition from slip to non-slip conditions, the belt and tangential pulley velocities are equal.

The block implements these equations for four different slip conditions.

Condition	Equations
Belt slips on both secondary and primary pulleys	$(J_{pri} + J_i)\dot{\omega}_{pri} = T_{app_pri} - T_{BoP_pri} - b_{pri}\omega_{pri}$ $J_{sec}\dot{\omega}_{sec} = T_{app_sec} - T_{BoP_sec} - b_{sec}\omega_{sec}$ $m_b\dot{v}_b = \frac{T_{BoP_pri}}{r_{pri}} + \frac{T_{BoP_sec}}{r_{sec}} - b_b v_b$ $r_{pri}\omega_{pri} \neq v_b$ $r_{sec}\omega_{sec} \neq v_b$
Belt slips on only the primary pulley	$(J_{pri} + J_i)\dot{\omega}_{pri} = T_{app_pri} - T_{BoP_pri} - b_{pri}\omega_{pri}$ $\left(m_b + \frac{J_{sec}}{r_{sec}^2}\right)\dot{v}_b = \frac{T_{BoP_pri}}{r_{pri}} + \frac{T_{BoP_sec}}{r_{sec}} - \left(b_b + \frac{b_{sec}}{r_{sec}^2}\right)v_b$ $\omega_{sec} = \frac{v_b}{r_{sec}}$ $r_{pri}\omega_{pri} \neq v_b$ $T_{BoP_pri} = \text{sgn}(r_{pri}\omega_{pri} - v_b)T_{fric}(r_{pri}, \mu_{kin})$ $ T_{BoP_sec} < T_{fric}(r_{sec}, \mu_{static})$
Belt slips on only the secondary pulley	$\left(m_b + \frac{J_{pri} + J_i}{r_{pri}^2}\right)\dot{v}_b = \frac{T_{app_pri}}{r_{pri}} + \frac{T_{BoP_sec}}{r_{sec}} - \left(b_b + \frac{b_{pri}}{r_{pri}^2}\right)v_b$ $J_{sec}\dot{\omega}_b = T_{app_sec} + T_{BoP_sec} - b_{sec}\omega_{sec}$ $\omega_{pri} = \frac{v_b}{r_{pri}}$ $r_{sec}\omega_{sec} \neq v_b$ $T_{BoP_sec} = \text{sgn}(r_{sec}\omega_{sec} - v_b)T_{fric}(r_{sec}, \mu_{kin})$ $ T_{BoP_pri} < T_{fric}(r_{pri}, \mu_{static})$
Belt does not slip	$\left(m_b + \frac{J_{sec}}{r_{sec}^2} + \frac{J_{pri} + J_i}{r_{pri}^2}\right)\dot{v}_b = \frac{T_{app_pri}}{r_{pri}} + \frac{T_{app_sec}}{r_{sec}} - \left(b_b + \frac{b_{sec}}{r_{sec}^2} + \frac{b_{pri}}{r_{pri}^2}\right)v_b$ $\omega_{pri} = \frac{v_b}{r_{pri}}$ $\omega_{sec} = \frac{v_b}{r_{sec}}$ $ T_{BoP_pri} < T_{fric}(r_{pri}, \mu_{static})$ $ T_{BoP_sec} < T_{fric}(r_{sec}, \mu_{static})$

Condition	Equations
Slip direction	$PriSlipDir = \begin{cases} 0 & r_{pri}\omega_{pri} = v_b \\ 1 & r_{pri}\omega_{pri} > v_b \\ -1 & r_{pri}\omega_{pri} < v_b \end{cases}$ $SecSlipDir = \begin{cases} 0 & r_{sec}\omega_{sec} = v_b \\ 1 & r_{sec}\omega_{sec} > v_b \\ -1 & r_{sec}\omega_{sec} < v_b \end{cases}$

The equations use these variables.

T_{BoP_pri}, T_{BoP_sec}	Belt torque acting on the primary and secondary pulleys, respectively
T_{app_pri}, T_{app_sec}	Torque applied to primary and secondary pulleys, respectively
J_{pri}, J_{sec}	Primary and secondary pulley rotational inertias, respectively
b_{pri}, b_{sec}	Primary and secondary pulley rotational viscous damping, respectively
F_{ax}	Pulley clamp force
μ	Coefficient of friction
μ_{kin}, μ_{static}	Coefficient of kinetic and static friction
v_b, a_b	Linear speed and acceleration of the belt, respectively
m_b	Total belt mass
r_{pri}, r_{sec}	Radii of the primary and secondary pulleys, respectively
Φ_{wrap}	Wrap angle of belt to pulley contact point
$\Phi_{wrap_pri}, \Phi_{wrap_sec}$	Primary and secondary pulley wrap angles, respectively

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks	PwrEng	Engine power	P_{eng}	$\omega_i T_i$
	<ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrDiffrntl	Differential power	P_{diff}	$\omega_o T_o$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input Negative signals indicate a loss 	PwrBltLoss	Belt slip power loss	$P_{btlloss}$	$(J_{in} + J_{pri})\dot{\omega}_{pri}\omega_{pri} + J_{sec}\dot{\omega}_{sec}\omega_{sec} + m_b\dot{v}_b v_b + b_{pri}\omega_{pri}^2 + b_{sec}\omega_{sec}^2 + b_b v_b^2 - T_{app_pri}\omega_{pri} - T_{app_sec}\omega_{sec}$

Bus Signal		Description	Variable	Equations
	PwrGearInLoss	Input planetary gear mechanical power loss	$P_{grinloss}$	$-\left \omega_i T_i - T_{app_pri} \omega_{pri}\right $
	PwrGearOutLoss	Output gear reduction mechanical power loss	$P_{groutloss}$	$-\left \omega_o T_o - T_{app_sec} \omega_{sec}\right $
	PwrDampLoss	Mechanical damping loss	$P_{damploss}$	$-b_{pri} \omega_{pri}^2 - b_{sec} \omega_{sec}^2 - b_b v_b^2$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredTrans	P_{str}	$(J_{in} + J_{pri}) \dot{\omega}_{pri} \omega_{pri} + J_{sec} \dot{\omega}_{sec} \omega_{sec} + m_b \dot{v}_b v_b$

The equations use these variables.

T_{app_pri}, T_{app_sec}	Torque applied to primary and secondary pulleys, respectively
T_i, T_o	Input and output drive shaft torque, respectively
J_{pri}, J_{sec}	Primary and secondary pulley rotational inertias, respectively
b_{pri}, b_{sec}	Primary and secondary pulley rotational viscous damping, respectively
$\omega_{pri}, \omega_{sec}$	Primary and secondary pulley speed, respectively
ω_i, ω_o	Input and output drive shaft speed, respectively
v_b, a_b	Linear speed and acceleration of the belt, respectively
r_{pri}, r_{sec}	Radii of the primary and secondary pulleys, respectively

Ports

Inputs

Dir — Direction request

scalar

Direction request, Dir_{req} , controlling the direction. The block filters the request to determine the direction, forward or reverse. Dir equals 1 for forward motion. Dir equals -1 for reverse.

$$Dir = \begin{cases} 1 & \text{when } Dir_{req} \geq 0 \\ -1 & \text{when } Dir_{req} < 0 \end{cases}$$

PLlyRatioReq — Pulley ratio request

scalar

CVT pulley ratio request, $ratio_{request}$.

Dependencies

To create this port, for the **Control mode** parameter, select `Ideal` integrated controller.

PriDisp – Primary pulley displacement

scalar

Variator primary pulley displacement, x_{pri} , in m.

Dependencies

To create this port, for the **Control mode** parameter, select `External` control.

SecDisp – Secondary pulley displacement

scalar

Variator secondary pulley displacement, x_{sec} , in m.

Dependencies

To create this port, for the **Control mode** parameter, select `External` control.

EngTrq – Input drive shaft torque

scalar

External torque applied to the input drive shaft, T_i , in N·m.

DiffTrq – Output drive shaft torque

scalar

External torque applied to the output drive shaft, T_o , in N·m.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable	Units
EngTrq	Input shaft torque	T_i	N·m
DiffTrq	Output shaft torque	T_o	N·m
EngSpd	Input shaft speed	ω_i	rad/s
DiffSpd	Output shaft speed	ω_o	rad/s
PriRadius	Primary pulley radius	r_{pri}	m
PriPhi	Primary pulley wrap angle	Φ_{pri}	rad
SecRadius	Secondary pulley radius	r_{sec}	m
SecPhi	Secondary pulley wrap angle	Φ_{sec}	rad
BltLngthDelta	Change in belt length	ΔL	m
BltLngth	Belt length	L	m
BltLngthInit	Initial belt length	L_o	m

Signal		Description	Variable	Units	
BltOnPriTrq		Belt torque acting on the primary pulley	T_{BoP_pri}	N·m	
BltOnSecTrq		Belt torque acting on the secondary pulley	T_{BoP_sec}	N·m	
BltVel		Linear speed of the belt	v_b	m/s	
PriAngVel		Primary pulley speed	ω_{pri}	rad/s	
SecAngVel		Secondary pulley speed	ω_{sec}	rad/s	
PriSlipDir		Primary pulley slip direction indicator	$PriSlipDir$	N/A	
SecSlipDir		Secondary pulley slip direction indicator	$SecSlipDir$	N/A	
TransSpdRatio		Total no-slip gear ratio	N_{final}	N/A	
PwrInfo	PwrTrnsfrd	PwrEng	Engine power	P_{eng}	W
		PwrDiffrentl	Differential power	P_{diff}	W
	PwrNotTrnsfrd	PwrBltLoss	Belt slip power loss	$P_{bltloss}$	W
		PwrGearInLoss	Input planetary gear mechanical power loss	$P_{grinloss}$	W
		PwrGearOutLoss	Output gear reduction mechanical power loss	$P_{grouloss}$	W
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	W
	PwrStored	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str}	W

EngSpd – Input drive shaft speed

scalar

Input drive shaft angular speed, ω_i , in rad/sec.**DiffSpd – Output drive shaft speed**

scalar

Output drive shaft angular speed, ω_o , in rad/sec.**Parameters****Control mode – External or internal**

Ideal integrated controller (default) | External control

Specify the control method, either internal or external.

Dependencies

This table summarizes the port and input model configurations.

Control Mode	Creates Ports
Ideal integrated controller	PlyRatioReq
External control	PriDisp SecDisp

Kinematics

Maximum variator primary pulley radius, rp_max – Radius

.08 (default) | scalar

Maximum variator primary pulley radius, rp_{max} , in m.

Maximum variator secondary pulley radius, rs_max – Radius

.07 (default) | scalar

Maximum variator secondary pulley radius, rs_{max} , in m.

Minimum variator primary pulley radius, rp_min – Radius

.03 (default) | scalar

Minimum variator primary pulley radius, rp_{min} , in m.

Minimum variator secondary pulley radius, rs_min – Radius

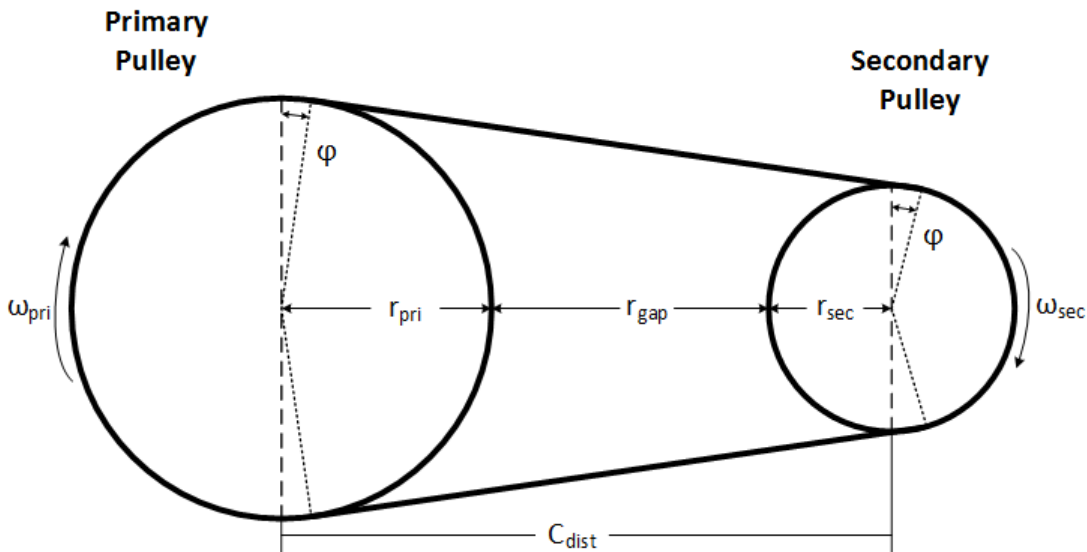
.03 (default) | scalar

Minimum variator secondary pulley radius, rs_{min} , in m.

Gap distance between variator pulleys, $rgap$ – Specify crown wheel connection

.025 (default) | scalar

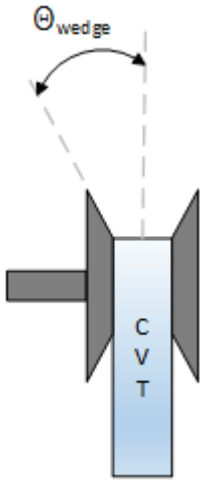
The gap between the secondary and primary pulleys, r_{gap} , in m. The figure shows the pulley geometry.



Variator wedge angle, $thetawedge$ – Specify crown wheel connection

11 (default) | scalar

Variator wedge angle, θ_{wedge} , in deg.



Dynamics

Primary pulley inertia, J_{pri} – Inertia

0.1 (default) | scalar

Primary pulley inertia, J_{pri} , in $\text{kg}\cdot\text{m}^2$.

Secondary pulley inertia, J_{sec} – Inertia

0.1 (default) | scalar

Secondary pulley inertia, J_{sec} , in $\text{kg}\cdot\text{m}^2$.

Primary pulley damping coefficient, b_{pri} – Damping

0.001 (default) | scalar

Primary pulley damping coefficient, b_{pri} , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Secondary pulley damping coefficient, b_{sec} – Damping

0.001 (default) | scalar

Secondary pulley damping coefficient, b_{sec} , in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.

Belt damping coefficient, b_b – Damping

0.0025 (default) | scalar

Belt damping coefficient, b_b , in kg/s .

Static friction coefficient, μ_{static} – Friction

0.3 (default) | scalar

Static friction coefficient between the belt and primary pulley, μ_{static} , dimensionless.

Kinetic friction coefficient, μ_{kin} – Friction

0.2 (default) | scalar

Kinetic friction coefficient between the belt and primary pulley, μ_{kin} , dimensionless.

Belt mass, m_b — Mass

3 (default) | scalar

Belt mass, m_b , in kg.**Pulley clamp force, F_ax — Pulley clamp force**

5000 (default) | scalar

Pulley clamp force, F_{ax} , in N.**Reverse and Output Ratio****Forward inertia, J_fwd — Inertia**

0.1 (default) | scalar

Forward inertia, J_{fwd} , in $\text{kg}\cdot\text{m}^2$.**Reverse inertia, J_rev — Inertia**

0.1 (default) | scalar

Reverse inertia, J_{rev} , in $\text{kg}\cdot\text{m}^2$.**Forward efficiency, eta_fwd — Efficiency**

0.95 (default) | scalar

Forward efficiency, η_{fwd} , dimensionless.**Reverse efficiency, eta_rev — Efficiency**

0.95 (default) | scalar

Reverse efficiency, η_{rev} , dimensionless.**Reverse gear ratio, N_rev — Ratio**

2 (default) | scalar

Reverse gear ratio, N_{rev} , dimensionless.**Shift time constant, tau_s — Constant**

.01 (default) | scalar

Shift time constant, τ_s , in s.**Output gear ratio, N_o — Ratio**

2 (default) | scalar

Output gear ratio, N_o , dimensionless.**Output gear efficiency, eta_o — Efficiency**

0.98 (default) | scalar

Output gear efficiency, η_o , dimensionless.**Version History****Introduced in R2017a**

References

- [1] Ambekar, Ashok G. *Mechanism and Machine Theory*. New Delhi: Prentice-Hall of India, 2007.
- [2] Bensen, B. *Efficiency optimization of the push-belt CVT by variator slip control*. Ph.D. Thesis. Eindhoven University of Technology, 2006.
- [3] *CVT How Does It Work*. CVT New Zealand 2010 Ltd, 10 Feb. 2011. Web. 25 Apr. 2016.
- [4] Klaassen, T. W. G. L. *The Impact CVT: Dynamics and Control of an Electromechanically Actuated CVT*. Ph.D. Thesis. Eindhoven University of Technology, 2007.
- [5] Sakagami, K. *Prediction of Friction Drive Limit of Metal V-Belt*. Warrendale, PA: SAE International Journal of Engines 8(3):1408-1416, 2015.

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

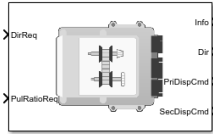
See Also

CVT Controller

CVT Controller

Continuously variable transmission controller

Library: Powertrain Blockset / Transmission / Transmission Controllers



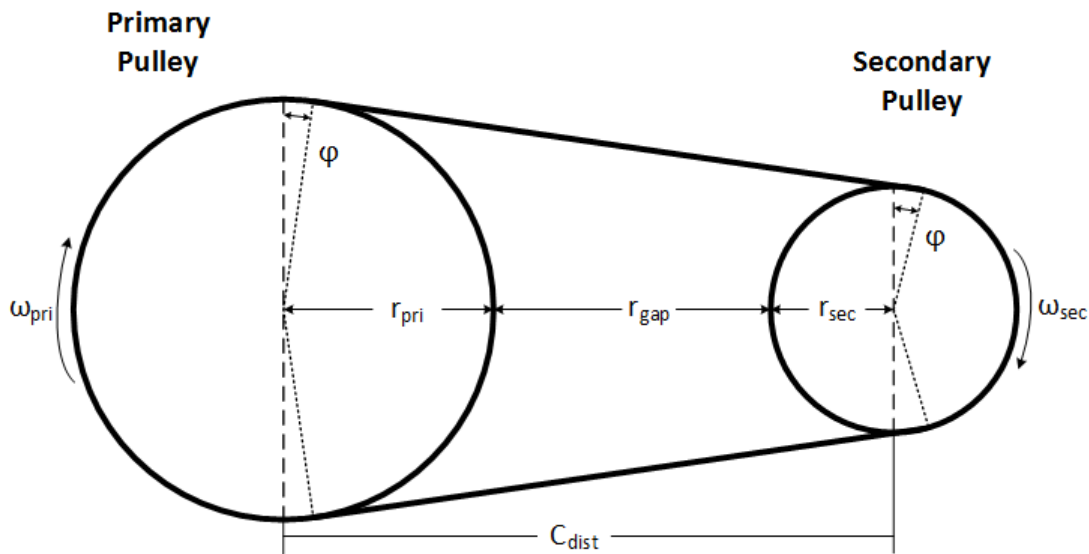
Description

The CVT Controller block implements a push belt continuously variable transmission (CVT) controller. The block uses standard pulley and geometric equations to calculate the kinematic setpoints for the CVT variator. You can use the block to control a CVT.

Pulley Kinematics

Using the physical dimensions of the system, the block calculates the primary and secondary variator positions that meet the pulley ratio request.

The figure and equations summarize the geometric dependencies.



$$\begin{aligned}
C_{dist} &= rp_{max} + r_{gap} + r_{sec_max} \\
L_0 &= f(rp_{max}, rs_{max}, rp_{min}, rs_{min}, C_{dist}) \\
ratio_{command} &= f(ratio_{request}, ratio_{max}, ratio_{min}) \\
r_{pri} &= f(r_0, ratio_{command}, C_{dist}) \\
r_{sec} &= f(r_0, ratio_{command}, C_{dist}) \\
x_{pri} &= f(r_0, r_{pri}, \theta_{wedge}) \\
x_{sec} &= f(r_0, r_{sec}, \theta_{wedge})
\end{aligned}$$

The equations use these variables.

$ratio_{request}$	Pulley gear ratio request
$ratio_{command}$	Pulley gear ratio command, based on request and physical limitations
r_{gap}	Gap distance between variator pulleys
C_{dist}	Distance between variator pulley centers
rp_{max}	Maximum variator primary pulley radius
rs_{max}	Maximum variator secondary pulley radius
rp_{min}	Minimum variator primary pulley radius
rs_{min}	Minimum variator secondary pulley radius
r_0	Initial pulley radii with gear ratio of 1
L_0	Initial belt length, resulting from variator specification
x_{pri}	Variator primary pulley displacement, resulting from controller request
x_{sec}	Variator secondary pulley displacement, resulting from controller request
r_{pri}	Variator primary pulley radius, resulting from controller request
r_{sec}	Variator secondary pulley radius, resulting from controller request
Θ_{wedge}	Variator wedge angle
Φ	Angle of belt to pulley contact point
L	Belt length, resulting from variator position

Ports

Inputs

DirReq – Direction request

scalar

Direction request, Dir_{req} , controlling the direction, either forward or reverse. Dir equals 1 for forward motion. Dir equals -1 for reverse.

$$Dir = \begin{cases} 1 & \text{when } Dir_{req} \geq 0 \\ -1 & \text{when } Dir_{req} < 0 \end{cases}$$

PLlyRatioReq – Pulley ratio request

scalar

CVT pulley ratio request, $ratio_{request}$.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units
Radius	PriRadius	Variator primary pulley radius, resulting from controller request	r_{pri}	m
	SecRadius	Variator secondary pulley radius, resulting from controller request	r_{sec}	m
	InitPllyRadius	Initial pulley radii with gear ratio of 1	r_o	m
RatioAdj		Pulley gear ratio command, based on request and physical limitations	$ratio_{command}$	N/A
RatioMax		Maximum pulley ratio	$ratio_{max}$	N/A
RatioMin		Minimum pulley ratio	$ratio_{min}$	N/A
PriDispCmd		Variator primary pulley displacement, resulting from controller request	x_{pri}	m
SecDispCmd		Variator secondary pulley displacement, resulting from controller request	x_{sec}	m

Dir — Direction request

scalar

Direction request, Dir_{req} , controlling the direction, either forward or reverse. Dir equals 1 for forward motion. Dir equals -1 for reverse.

$$Dir = \begin{cases} 1 & \text{when } Dir_{req} \geq 0 \\ -1 & \text{when } Dir_{req} < 0 \end{cases}$$

PriDispCmd — Primary pulley displacement

scalar

Variator primary pulley displacement, x_{pri} , in m.

SecDispCmd — Secondary pulley displacement

scalar

Variator secondary pulley displacement, x_{sec} , in m.

Parameters

Kinematics

Maximum variator primary pulley radius, rp_max – Radius

.08 (default) | scalar

Maximum variator primary pulley radius, rp_{max} , in m.

Maximum variator secondary pulley radius, rs_max – Radius

.07 (default) | scalar

Maximum variator secondary pulley radius, rs_{max} , in m.

Minimum variator primary pulley radius, rp_min – Radius

.03 (default) | scalar

Minimum variator primary pulley radius, rp_{min} , in m.

Minimum variator secondary pulley radius, rs_min – Radius

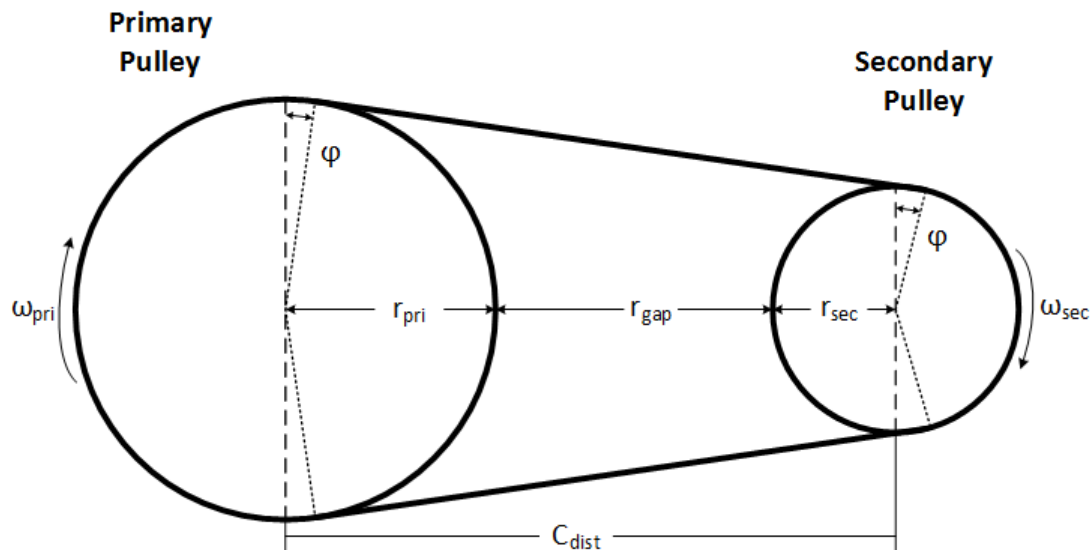
.03 (default) | scalar

Minimum variator secondary pulley radius, rs_{min} , in m.

Gap distance between variator pulleys, $rgap$ – Specify crown wheel connection

.025 (default) | scalar

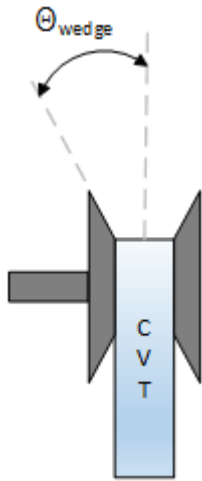
The gap between the secondary and primary pulleys, r_{gap} , in m. The figure shows the pulley geometry.



Variator wedge angle, θ_{wedge} – Specify crown wheel connection

11 (default) | scalar

Variator wedge angle, θ_{wedge} , in deg.



Version History

Introduced in R2017a

References

- [1] Ambekar, Ashok G. *Mechanism and Machine Theory*. New Delhi: Prentice-Hall of India, 2007.
- [2] Bensen, B. *Efficiency optimization of the push-belt CVT by variator slip control*. Ph.D. Thesis. Eindhoven University of Technology, 2006.
- [3] *CVT How Does It Work*. CVT New Zealand 2010 Ltd. February 10, 2011. Accessed April 25, 2016.
- [4] Klaassen, T. W. G. L. *The Empact CVT: Dynamics and Control of an Electromechanically Actuated CVT*. Ph.D. Thesis. Eindhoven University of Technology, 2007.

Extended Capabilities

C/C++ Code Generation

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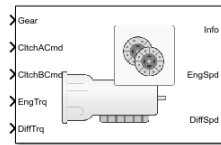
See Also

Continuously Variable Transmission

Dual Clutch Transmission

Dual clutch transmission that applies torque to the drive shaft

Library: Powertrain Blockset / Transmission / Transmission Systems



Description

The Dual Clutch Transmission block implements a dual clutch transmission (DCT). In a DCT, two clutches apply mechanical torque to the drive shaft. Odd gears engage one clutch, while even gears engage the secondary clutch. The number of gears is specified via an integer vector with corresponding gear ratios, inertias, viscous damping, and efficiency factors. The clutch and synchronization engagement rates are linear and adjustable. You can provide external clutch signals or configure the block to generate idealized internal clutch signals. The block implements the transmission model with minimal parameterization or computational cost.

Use the block to model a simplified automated manual transmission (AMT) for:

- Power and torque capacity sizing
- Determining gear ratio impact on fuel economy and performance

To determine the rotational drive shaft speed and reaction torque, the Dual Clutch Transmission block calculates:

- Clutch lock-up and clutch friction
- Locked rotational dynamics
- Unlocked rotational dynamics

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

Clutch Control

The DCT delivers drive shaft torque continuously by controlling the pressure signals from both clutches. If you select **Control mode** parameter `Ideal integrated controller`, the block generates idealized clutch pressure signals. The block uses the maximum pressure from each clutch

to approximate the single-clutch commands that result in equivalent drive shaft torque. To use your own clutch control signals, select **Control mode** parameter External control.

Clutch Lock-Up and Clutch Friction

Based on the clutch lock-up condition, the block implements one of these friction models.

If	Clutch Condition	Friction Model
$\omega_i \neq N\omega_d$ or $T_S < T_f - Nw_i b_i $	Unlocked	$T_f = T_k$ where, $T_k = F_c R_{eff} \mu_k \tanh\left[4\left(\frac{w_i}{N} - w_d\right)\right]$ $T_s = F_c R_{eff} \mu_s$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$
$\omega_i = N\omega_t$ and $T_S \geq T_f - Nb_i \omega_i $	Locked	$T_f = T_s$

The equations use these variables.

- ω_t Output drive shaft speed
- ω_i Input drive shaft speed
- ω_d Drive shaft speed
- b_i Viscous damping
- F_c Applied clutch force
- N Engaged gear
- T_f Frictional torque
- T_k Kinetic frictional torque
- T_s Static frictional torque
- R_{eff} Effective clutch radius
- R_o Annular disk outer radius
- R_i Annular disk inner radius
- μ_s Coefficient of static friction
- μ_k Coefficient of kinetic friction

Locked Rotational Dynamics

To model the rotational dynamics when the clutch is locked, the block implements these equations.

$$\dot{\omega}_d J_N = \eta_N T_d - \frac{\omega_i}{N} b_N + N T_i$$

$$\omega_i = N \omega_d$$

The block determines the input torque, T_i , through differentiation.

The equations use these variables.

ω_i	Input drive shaft speed
ω_d	Drive shaft speed
N	Engaged gear
b_N	Engaged gear viscous damping
J_N	Engaged gear inertia
η_N	Engaged gear efficiency
T_d	Drive shaft torque
T_i	Applied input torque

Unlocked Rotational Dynamics

To model the rotational dynamics when the clutch is unlocked, the block implements this equation.

$$\dot{\omega}_d J_N = N T_i - \omega_d b_N + T_d$$

where:

ω_d	Drive shaft speed
N	Engaged gear
b_N	Engaged gear viscous damping
J_N	Engaged gear inertia
T_d	Drive shaft torque
T_i	Applied input torque

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrIn fo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrEng	Engine power	P_{eng}	$\omega_i T_i$
		PwrDiffrntl	Differential power	P_{diff}	$\omega_d T_d$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred <ul style="list-style-type: none"> Positive signals indicate an input 	PwrEffLoss	Mechanical power loss	$P_{effloss}$	$\omega_d T_d (\eta_N - 1)$
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	$-b_N \omega_d^2 - b_{in} \omega_i^2$

Bus Signal		Description	Variable	Equations	
	<ul style="list-style-type: none"> Negative signals indicate a loss 	PwrClutchLoss	Clutch power loss	P_{mech}	When locked: 0 When unlocked: $-T_k(\omega_i - N\omega_d)$
	PwrStored — Stored energy rate of change <ul style="list-style-type: none"> Positive signals indicate an increase Negative signals indicate a decrease 	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str}	When locked: $\dot{\omega}_i\omega_i(J_{in} + \frac{J_N}{N^2})$ When unlocked: $J_{in}\dot{\omega}_i\omega_i + J_N\dot{\omega}_d\omega_d$

The equations use these variables.

b_N	Engaged gear viscous damping
J_N	Engaged gear rotational inertia
J_{in}	Flywheel rotational inertia
η_N	Engaged gear efficiency
N	Engaged gear ratio
T_i	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper
T_d	Applied load torque, typically from the differential or drive shaft
ω_d	Initial input drive shaft rotational velocity
$\omega_i, \dot{\omega}_i$	Applied drive shaft angular speed and acceleration

Ports

Inputs

Gear — Gear number to engage

scalar

Integer value of gear number to engage.

ClutchACmd — Command for odd-numbered gears

scalar

Clutch pressure command for odd-numbered gears, between 0 and 1.

Dependencies

To create this port, select **Control mode** parameter External control.

ClutchBCmd — Command for even-numbered gears

scalar

Clutch pressure command for even-numbered gears, between 0 and 1.

Dependencies

To create this port, select **Control mode** parameter External control.

EngTrq – Applied torque

scalar

Applied input torque, T_i , typically from the engine crankshaft or dual mass flywheel damper, in N·m.

DiffTrq – Applied torque

scalar

Applied load torque, T_d , typically from the drive shaft, in N·m.

Temp – Oil temperature

scalar

Oil temperature, in K. To determine the efficiency, the block uses a 4D lookup table that is a function of:

- Gear
- Input torque
- Input speed
- Oil temperature

Dependencies

To create this port, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Output**Info – Bus signal**

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units
Eng	EngTrq	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper	T_i	N·m
	EngSpd	Applied drive shaft angular speed input	ω_i	rad/s
Diff	DiffTrq	Applied load torque, typically from the differential	T_d	N·m
	DiffSpd	Drive shaft angular speed output	ω_d	rad/s
Cltch	CltchForce	Applied clutch force	F_c	N
	CltchLocked	Clutch state	NA	NA

Signal		Description	Variable	Units	
Trans	TransSpd Ratio	Input to output speed ratio at time t	$\Phi(t)$	NA	
	TransEta	Ratio of output power to input power	η_N	NA	
	TransGearCmd	Commanded gear	N_{cmd}	NA	
	TransGear	Engaged gear	N	NA	
PwrInfo	PwrTrnsfrd	PwrEng	Engine power	P_{eng}	W
		PwrDiffrentl	Differential power	P_{diff}	W
	PwrNotTrnsfrd	PwrEffLoss	Mechanical power loss	$P_{effloss}$	W
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	W
		PwrClutchLoss	Clutch power loss	P_{mech}	W
	PwrStored	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str}	W

EngSpd — Angular speed

scalar

Drive shaft angular speed, ω_d , in rad/s.

DiffSpd — Angular speed

scalar

Drive shaft angular speed, ω_d , in rad/s.

Parameters

Control mode — Specify control mode

External control (default) | Ideal integrated controller

The DCT delivers drive shaft torque continuously by controlling the pressure signals from both clutches. If you select **Control mode** parameter **Ideal integrated controller**, the block generates idealized clutch pressure signals. The block uses the maximum pressure from each clutch to approximate the single-clutch commands that result in equivalent drive shaft torque. To use your own clutch control signals, select **Control mode** parameter **External control**.

Dependencies

This table summarizes the port configurations.

Control Mode	Creates Ports
External control	ClutchACmd
	ClutchBCmd

Efficiency factors – Specify efficiency calculation

Gear only (default) | Gear, input torque, input speed, and temperature

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

Dependencies

Setting Parameter To	Enables
Gear only	Efficiency vector, eta
Gear, input torque, input speed, and temperature	Efficiency torque breakpoints, Trq_bpts Efficiency speed breakpoints, omega_bpts Efficiency temperature breakpoints, Temp_bpts Efficiency lookup table, eta_tbl

Transmission

Input shaft inertia, Jin – Inertia

0.1 (default) | scalar

Input shaft inertia, in kg·m².

Input shaft damping, bin – Damping

0.001 (default) | scalar

Input shaft damping, in N·m·s/rad.

Initial input velocity, omegain_o – Angular velocity

0 (default) | scalar

Angular velocity, in rad/s.

Efficiency torque breakpoints, Trq_bpts – Breakpoints

[25 50 75 100 150 200 250] (default) | vector

Torque breakpoints for efficiency table, in N·m.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency speed breakpoints, omega_bpts — Breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | vector

Speed breakpoints for efficiency table, in rad/s.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency temperature breakpoints, Temp_bpts — Breakpoints

[313 358] (default) | vector

Temperature breakpoints for efficiency table, in K.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Gear number vector, G — Specify number of transmission speeds

[-1, 0, 1, 2, 3, 4, 5, 6, 7, 8] (default) | vector

Vector of integers used to specify the number of transmission speeds. Neutral gear is 0. For example, you can set these parameter values.

To Specify	Set Gear number, G to
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]
Three transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3]
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Gear ratio vector, N — Ratio of input speed to output speed

[-4.70, 4.70, 4.700, 3.130, 2.100, 1.670, 1.290, 1.000, 0.840, 0.670] (default) | vector

Vector of gear ratios (that is, input speed to output speed) with indices corresponding to the ratios specified in **Gear number, G**. For neutral, set the gear ratio to 1. For example, you can set these parameter values.

To Specify Gear Ratios for	Set Gear number, G to	Set Gear ratio, N to
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]	[1, 4.47, 2.47, 1.47, 1]

To Specify Gear Ratios for	Set Gear number, G to	Set Gear ratio, N to
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]	[-4.47, 1, 4.47, 2.47, 1.47, 1, 0.8]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Transmission inertia vector, Jout – Gear rotational inertia

[0.08 0.08 0.08 0.04 0.02 0.01 0.01 0.01 0.01 0.01] (default) | vector

Vector of gear rotational inertias, with indices corresponding to the inertias specified in **Gear number, G**, in kg·m². For example, you can set these parameter values.

To Specify Inertia for	Set Gear number, G to	Set Inertia, J to
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.01, 2.28, 2.04, 0.32, 0.028]
Inertia for five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[2.28, 0.01, 2.28, 2.04, 0.32, 0.028, 0.01]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Damping vector, bout – Gear viscous damping coefficient

[.003 .001 .003 .0025 .002 .001 .001 .001 .001 .001] (default) | vector

Vector of gear viscous damping coefficients, with indices corresponding to the coefficients specified in **Gear number, G**, in N·m·s/rad. For example, you can set these parameter values.

To Specify Damping for	Set Gear number, G to	Set Damping, b to
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.001, 0.003, 0.0025, 0.002, 0.001]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.003, 0.001, 0.003, 0.0025, 0.002, 0.001, 0.001]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Efficiency vector, eta – Gear efficiency

[0.930, 0.930, 0.930, 0.940, 0.947, 0.948, 0.946, 0.943, 0.940, 0.935] (default) | vector

Vector of gear mechanical efficiency, with indices corresponding to the efficiencies specified in **Gear number, G**. For example, you can set these parameter values.

To Specify Efficiency for	Set Gear number, G to	Set Efficiency, eta to
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.9, 0.9, 0.9, 0.9, 0.95]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.9, 0.9, 0.9, 0.9, 0.9, 0.95, 0.95]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Transmission inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear only.

Efficiency lookup table, eta_tbl – Gear efficiency

array

Table of gear mechanical efficiency, η_N as a function of gear, input torque, input speed, and temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Initial output velocity, omegaout_o – Transmission

0 (default) | scalar

Transmission initial output rotational velocity, ω_{to} , in rad/s. If you select **Clutch initially locked**, the block ignores the **Initial output velocity, omega_o** parameter value.

Initial gear, G_o – Engaged gear

0 (default) | scalar

Initial gear to engage, G_o .

Clutch and Synchronizer**Clutch pressure time constant, tauc – Time**

.02 (default) | scalar

Time required to engage and disengage the clutch during shift events, t_c , in s.

Synchronization time, ts – Time

.2 (default) | scalar

Time required for gear selection and synchronization, t_s , in s.

Clutch time, tc – Time

.5 (default) | scalar

Time required to engage clutch, t_c , in s.

Dependencies

To create this parameter, select **Control mode** parameter Ideal integrated controller.

Effective clutch radius, R – Radius

.25 (default) | scalar

The effective radius, R_{eff} , used with the applied clutch friction force to determine the friction force, in m. The effective radius is defined as:

$$R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$$

The equation uses these variables.

R_o Annular disk outer radius

R_i Annular disk inner radius

Clutch force gain, K_c – Force

5e4 (default) | scalar

Open loop lock-up clutch gain, K_c , in N.

Clutch static friction coefficient, μ_s – Coefficient

0.3 (default) | scalar

Dimensionless clutch disc coefficient of static friction, μ_s .

Clutch kinematic friction coefficient, μ_k – Coefficient

0.25 (default) | scalar

Dimensionless clutch disc coefficient of kinetic friction, μ_k .

Clutch initially locked – Select to initially lock clutch

off (default) | on

Selecting this parameter initially locks the clutch.

Dependencies

To create this parameter, select **Control mode** parameter Ideal integrated controller.

Synchronizer initially locked – Select to initially lock synchronizer

off (default) | on

Selecting this parameter initially locks the synchronizer.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

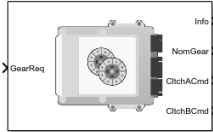
See Also

DCT Controller | Automated Manual Transmission

DCT Controller

Dual clutch transmission controller

Library: Powertrain Blockset / Transmission / Transmission Controllers



Description

The DCT Controller block implements a dual clutch transmission (DCT) controller. You can specify the clutch open, close, and synchronization timing parameters. The block determines the clutch commands using integrator-based timers and latching logic that is based on the specified timing parameters and gear request.

Ports

Inputs

GearReq — Gear number to engage

scalar

Gear number request, G_{req} .

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal	Description	Variable
GearReq	Gear number request	G_{req}
GearEngd	Nominal gear commanded by the controller	G_o
GearEffct	Effective gear	NA
ClutchACmd	Clutch pressure command for odd-numbered gears, between 0 and 1	NA
ClutchBCmd	Clutch pressure command for even-numbered gears, between 0 and 1	NA

NomGear — Nominal gear for shifting

scalar

Nominal gear for shifting. The Dual Clutch Transmission block uses this signal for the smooth application of inertial, efficiency, gear ratio, and damping parameters.

ClutchACmd – Command for odd-numbered gears

scalar

Clutch pressure command for odd-numbered gears, between 0 and 1.

ClutchBCmd – Command for even-numbered gears

scalar

Clutch pressure command for even-numbered gears, between 0 and 1.

Parameters**Initial gear, G_o – Engaged gear**

0 (default) | scalar

Initial gear to engage, G_o .**Clutch actuation time, t_c – Time**

.1 (default) | scalar

Time required to engage and disengage the clutch during shift events, t_c , in s.**Synchronizer time, t_s – Time**

.01 (default) | scalar

Time required for gear selection and synchronization, t_s , in s.**Sample period, dt – Time**

-1 (default) | scalar

Sample period, dt , in s.**Clutch initially locked – Select to initially lock clutch**

off (default) | on

Selecting this parameter initially locks the clutch.

Synchronizer initially locked – Select to initially lock synchronizer

off (default) | on

Selecting this parameter initially locks the synchronizer.

Version History

Introduced in R2017a

Extended Capabilities**C/C++ Code Generation**

Generate C and C++ code using Simulink® Coder™.

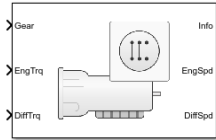
See Also

Dual Clutch Transmission | AMT Controller

Ideal Fixed Gear Transmission

Ideal fixed gear transmission without clutch or synchronization

Library: Powertrain Blockset / Transmission / Transmission Systems
Vehicle Dynamics Blockset / Powertrain / Transmission



Description

The Ideal Fixed Gear Transmission implements an idealized fixed-gear transmission without a clutch or synchronization. Use the block to model the overall gear ratio and power loss when you do not need a detailed transmission model, for example, in component-sizing, fuel economy, and emission studies. The block implements a transmission model with minimal parameterization or computational cost.

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

The block uses this equation to determine the transmission dynamics:

$$\dot{\omega}_i \frac{J_N}{N^2} = \eta_N \left(\frac{T_o}{N} + T_i \right) - \frac{\omega_i}{N^2} b_N$$

$$\omega_i = N \omega_o$$

The block filters the gear command signal:

$$\frac{G}{G_{cmd}}(s) = \frac{1}{\tau_s s + 1}$$

Neutral Gear

When **Initial gear number, G_o** is equal to 0, the initial gear is neutral. The block uses these parameters to decouple the input flywheel from the downstream gearing.

- **Initial input velocity, omega_o**
- **Initial neutral input velocity, omegainN_o**

The block uses these equations for the neutral gear speed and flywheel.

$$\dot{\omega}_{neutral} \frac{J_N}{N^2} = \eta_N \frac{T_o}{N} - \frac{\omega_{neutral}}{N^2} b_N$$

$$\omega_{neutral} = N\omega_o$$

$$\dot{\omega}_1 J_F = \eta_{@N} = 0 T_i - b_{@N} = 0 \omega_i$$

$$J_F = J_{@N} = 1 - J_{@N} = 0$$

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal		Description	Variable	Equations	
PwrInfo	PwrTrnsfrd — Power transferred between blocks • Positive signals indicate flow into block • Negative signals indicate flow out of block	PwrEng	Engine power	P_{eng}	$\omega_i T_i$
		PwrDiffntl	Differential power	P_{diff}	$\omega_o T_o$
	PwrNotTrnsfrd — Power crossing the block boundary, but not transferred • Positive signals indicate an input • Negative signals indicate a loss	PwrEffLoss	Mechanical power loss	$P_{effloss}$	$\omega_o T_o (\eta_N - 1)$
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	For $G=0$: $-\frac{b_N \omega_i^2}{ N^2 }$ For $G \neq 0$: $-b_N \omega_i^2 - \frac{b_N \omega_{neutral}^2}{ N^2 }$
PwrStored — Stored energy rate of change • Positive signals indicate an increase • Negative signals indicate a decrease	PwrStoredTrns	Rate change in rotational kinetic energy	P_{str}	For $G=0$: $\frac{J_N}{N^2} \dot{\omega}_i \omega_i$ For $G \neq 0$: $J_F \dot{\omega}_i \omega_i + \frac{J_N}{N^2} \dot{\omega}_{neutral} \omega_{neutral}$	

The equations use these variables.

- b_N Engaged gear viscous damping
- J_N Engaged gear rotational inertia
- J_F Flywheel rotational inertia
- η_N Engaged gear efficiency
- G Engaged gear number
- G_{cmd} Gear number to engage
- N Engaged gear ratio

T_i	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper
T_o	Applied load torque, typically from the differential or drive shaft
ω_o	Initial input drive shaft rotational velocity
$\omega_i, \dot{\omega}_i$	Applied drive shaft angular speed and acceleration
ω_{No}	Initial neutral gear input rotational velocity
$\omega_{neutral}$	Neutral gear drive shaft rotational velocity
τ_s	Shift time constant

Ports

Inputs

Gear — Gear number to engage

scalar

Integer value of gear number to engage, G_{cmd} .

EngTrq — Applied input torque

scalar

Applied input torque, T_i , typically from the engine crankshaft or dual mass flywheel damper, in N·m.

DiffTrq — Applied load torque

scalar

Applied load torque, T_o , typically from the differential, in N·m.

Temp — Oil temperature

scalar

Oil temperature, in K. To determine the efficiency, the block uses a 4D lookup table that is a function of:

- Gear
- Input torque
- Input speed
- Oil temperature

Dependencies

To enable this port, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Output

Info — Bus signal

bus

Bus signal containing these block calculations.

Signal		Description	Variable	Units	
Eng	EngTrq	Applied input torque, typically from the engine crankshaft or dual mass flywheel damper	T_i	N·m	
	EngSpd	Applied drive shaft angular speed input	ω_i	rad/s	
Diff	DiffTrq	Applied load torque, typically from the differential	T_o	N·m	
	DiffSpd	Drive shaft angular speed output	ω_o	rad/s	
Trans	TransSpdRatio	Input to output speed ratio at time t	$\Phi(t)$	N/A	
	TransEta	Ratio of output power to input power	η_N	N/A	
	TransGearCmd	Commanded gear	N_{cmd}	N/A	
	TransGear	Engaged gear	N	N/A	
PwrInfo	PwrTrnsfrd	PwrEng	Engine power	P_{eng}	W
		PwrDiffrentl	Differential power	P_{diff}	W
	PwrNotTrnsfrd	PwrEffLoss	Mechanical power loss	$P_{effloss}$	W
		PwrDampLoss	Mechanical damping loss	$P_{damploss}$	W
	PwrStored	PwrStoredTrans	Rate change in rotational kinetic energy	P_{str}	W

EngSpd — Angular speed

scalar

Applied drive shaft angular speed input, ω_i , in rad/s.

DiffSpd — Angular speed

scalar

Drive shaft angular speed output, ω_o , in rad/s.

Parameters

Efficiency factors – Specify efficiency calculation

Gear only (default) | Gear, input torque, input speed, and temperature

To specify the block efficiency calculation, for **Efficiency factors**, select either of these options.

Setting	Block Implementation
Gear only	Efficiency determined from a 1D lookup table that is a function of the gear.
Gear, input torque, input speed, and temperature	Efficiency determined from a 4D lookup table that is a function of: <ul style="list-style-type: none"> • Gear • Input torque • Input speed • Oil temperature

Dependencies

Setting Parameter To	Enables
Gear only	Efficiency vector, eta
Gear, input torque, input speed, and temperature	Efficiency torque breakpoints, Trq_bpts Efficiency speed breakpoints, omega_bpts Efficiency temperature breakpoints, Temp_bpts Efficiency lookup table, eta_tbl

Gear property interpolation method – Interpolation

Nearest (default) | Linear | Flat | Cubic spline

Method that the block uses to switch the gear ratio during gear shifting.

Transmission

Gear number vector, G – Specify number of transmission speeds

[-1,0,1,2,3,4,5] (default) | vector

Vector of integer gear commands used to specify the number of transmission speeds. Neutral gear is 0. For example, you can set these parameter values.

To Specify	Set Gear number, G To
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]
Three transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3]
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Efficiency torque breakpoints, Trq_bpts – Breakpoints

[25,50,75,100,150,200,250] (default) | vector

Torque breakpoints for efficiency table.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency speed breakpoints, omega_bpts – Breakpoints

[52.4 78.5 105 131 157 183 209 262 314 419 524] (default) | vector

Speed breakpoints for efficiency table.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Efficiency temperature breakpoints, Temp_bpts – Breakpoints

[313 358] (default) | vector

Temperature breakpoints for efficiency table.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Gear ratio vector, N – Ratio of input speed to output speed

[-4.47,4.47,4.47,2.47,1.47,1,0.8] (default) | vector

Vector of gear ratios (that is, input speed to output speed) with indices corresponding to the ratios specified in **Gear number, G**. For neutral, set the gear ratio to 1. For example, you can set these parameter values.

To Specify Gear Ratios For	Set Gear number, G To	Set Gear ratio, N To
Four transmission speeds, including neutral	[0, 1, 2, 3, 4]	[1, 4.47, 2.47, 1.47, 1]
Five transmission speeds, including neutral and reverse	[-1, 0, 1, 2, 3, 4, 5]	[-4.47, 1, 4.47, 2.47, 1.47, 1, 0.8]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Inertia vector, Jout – Gear rotational inertia

[0.128 0.01 0.128 0.1 0.062 0.028 0.01] (default) | vector

Vector of gear rotational inertias, J_N , with indices corresponding to the inertias specified in **Gear number, G**, in kg*m². For example, you can set these parameter values.

To Specify Inertia For	Set Gear number, G To	Set Inertia, J To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.01, 2.28, 2.04, 0.32, 0.028]
Inertia for five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[2.28, 0.01, 2.28, 2.04, 0.32, 0.028, 0.01]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Damping vector, b_{out} – Gear viscous damping coefficient

[.003 .001 .003 .0025 .002 .001 .001] (default) | vector

Vector of gear viscous damping coefficients, b_N , with indices corresponding to the coefficients specified in **Gear number**, **G**, in N·m·s/rad. For example, you can set these parameter values.

To Specify Damping For	Set Gear number, G To	Set Damping, b To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.001, 0.003, 0.0025, 0.002, 0.001]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.003, 0.001, 0.003, 0.0025, 0.002, 0.001, 0.001]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Efficiency vector, η_a – Gear efficiency

[0.9, 0.9, 0.9, 0.9, 0.9, 0.95, 0.95] (default) | vector

Vector of gear mechanical efficiency, η_N , with indices corresponding to the efficiencies specified in **Gear number**, **G**. For example, you can set these parameter values.

To Specify Efficiency For	Set Gear number, G To	Set Efficiency, η_a To
Four gears, including neutral	[0, 1, 2, 3, 4]	[0.9, 0.9, 0.9, 0.9, 0.95]
Five gears, including reverse and neutral	[-1, 0, 1, 2, 3, 4, 5]	[0.9, 0.9, 0.9, 0.9, 0.9, 0.95, 0.95]

Vector dimensions for the **Gear number vector**, **Gear ratio vector**, **Inertia vector**, **Damping vector**, and **Efficiency vector** parameters must be equal.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear only.

Efficiency lookup table, η_{a_tbl} – Gear efficiency

array

Table of gear mechanical efficiency, η_N as a function of gear, input torque, input speed, and temperature.

Dependencies

To enable this parameter, set **Efficiency factors** to Gear, input torque, input speed, and temperature.

Initial gear number, G_o – Gear

0 (default) | scalar

Initial gear number, G_o , dimensionless.**Initial output velocity, omega_o – Output speed**

0 (default) | scalar

Transmission initial output rotational velocity, ω_o , in rad/s.**Initial neutral input velocity, omegainN_o – Neutral gear input speed**

0 (default) | scalar

Initial neutral gear input rotational velocity, ω_{No} , in rad/s.**Shift time constant, tau_s – Time**

.01 (default) | scalar

Shift time constant, τ_s , in s.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

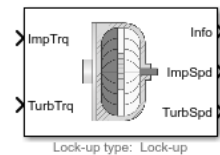
Generate C and C++ code using Simulink® Coder™.

See Also[Automated Manual Transmission](#) | [Dual Clutch Transmission](#) | [Continuously Variable Transmission](#)

Torque Converter

Three-part torque converter consisting of an impeller, turbine, and stator

Library: Powertrain Blockset / Transmission / Torque Converters



Description

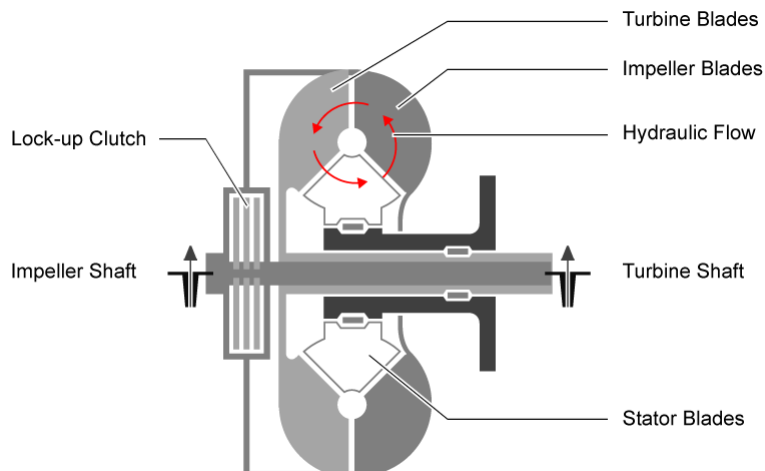
The Torque Converter block implements a three-part torque converter consisting of an impeller, turbine, and stator with an optional clutch lock-up capability. The block can simulate driving (power flowing from impeller to turbine) and coasting (power from turbine dissipated in torque converter hydraulic fluid).

You can specify torque converter characteristics:

- Speed ratio — Ratio of turbine angular speed to impeller angular speed
- Torque ratio — Ratio of turbine torque to impeller torque
- Capacity factor parameterization — Function of input speed or input torque

Optional clutch lock-up configurations include:

- No lock-up — Model fluid-coupling only
- Lock-up — Model automatic clutch engagement
- External lock-up — Model clutch pressure as input from an external signal



Dynamics

Clutch Lock-Up Condition and Clutch Friction

Based on the clutch lock-up condition, the block implements these friction models.

If	Clutch Condition	Friction Model
$\omega_i \neq \omega_t$ or $T_S < \left \frac{J_t}{(J_i + J_t)} [T_i + T_f - \omega_i(b_t + b_i)] \right $	Unlocked	$T_f = T_k$ where: $T_k = F_c R_{eff} m_k \tanh[4(\omega_i - \omega_t)]$ $T_s = F_c R_{eff} m_s$ $R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$
$\omega_i = \omega_t$ and $T_S \geq \left \frac{J_t}{(J_i + J_t)} [T_i + T_f - \omega_t(b_t + b_i) + \omega_t b_t] \right $	Locked	$T_f = T_s$

Locked Rotational Dynamics

To model the rotational dynamics if the clutch is locked, the block implements equations.

$$\dot{\omega}(J_i + J_t) = T_i - \omega(b_i + b_t) + T_{ext}$$

$$\omega = \omega_i = \omega_t$$

The rotational velocity represents both the impeller and turbine rotational velocities.

Unlocked Rotational Dynamics

To model the rotational dynamics if the clutch is unlocked, the block implements equations.

$$\dot{\omega}_i J_i = T_i - \omega_i b_i - T_f - T_p$$

$$\dot{\omega}_t J_t = T_{ext} - \omega_t b_t + T_f + T_t$$

$$T_p = \omega_i^2 \psi(\phi)$$

$$T_t = T_p \zeta(\phi)$$

To approximate the torque multiplication lag between the impeller and turbine, you can specify the parameter **Fluid torque response time constant (set to 0 to disable), tauc [s]**.

Power Accounting

For the power accounting, the block implements these equations.

Bus Signal	Description	Variable	Equations
PwrIn fo	PwrTrnsfrd — Power transferred between blocks <ul style="list-style-type: none"> Positive signals indicate flow into block Negative signals indicate flow out of block 	PwrImp	Applied impeller power P_{imp} $\omega_i T_i$
		PwrTur b	Applied turbine output power P_{turb} $\omega_t T_t$

Bus Signal		Description	Variable	Equations
PwrNotTrnsfrd — Power crossing the block boundary, but not transferred	PwrDampLoss	Mechanical damping loss	$P_{damploss}$	$-b_t\omega_t^2 - b_i\omega_i^2$
	PwrFluidCplingLoss	Heat loss to transmission fluid	P_{flloss}	$-(T_p\omega_i - T_{hyd}\omega_t)$
	PwrClutchLoss	Clutch slip power loss	$P_{cltloss}$	$-T_k(\omega_i - \omega_t)$
PwrStored — Stored energy rate of change	PwrStoredImp	Rate change in impeller rotational kinetic energy	P_{strimp}	$\dot{\omega}_i\omega_i J_i$
	PwrStoredTurb	Rate change in turbine rotational kinetic energy	$P_{strturb}$	$\dot{\omega}_t\omega_t J_t$

The block implements equations that use these variables.

T_f	Frictional torque
T_k	Kinetic frictional torque
T_s	Static frictional torque
T_i	Applied input torque
T_p	Impeller reaction torque
T_{ext}	Externally applied turbine torque
$\psi(\phi)$	Torque conversion capacity factor
$\zeta(\phi)$	Torque ratio
ω_i	Impeller rotational shaft speed
ω_t	Turbine rotational shaft speed
J_i	Impeller rotational inertia
J_t	Turbine rotational inertia
b_i	Impeller rotational viscous damping
b_t	Turbine rotational viscous damping
R_{eff}	Effective clutch radius
R_o	Annular disk outer radius
R_i	Annular disk inner radius

Ports

Inputs

ImpTrq — Applied impeller torque
scalar

Applied input torque, typically from the engine crankshaft or dual mass flywheel, in N·m.

TurbTrq – Applied turbine torque

scalar

Applied turbine torque, typically from the transmission, in N·m.

Clutch Force – Applied clutch force

scalar

Applied clutch force, typically from a hydraulic actuator, in N.

Dependencies

To create this port, select External lock-up input for the **Lock-up clutch configuration** parameter.

Output

Info – Bus signal

bus

Bus signal containing these block calculations.

Signal	Description		Units	
Imp	ImpTrq	Applied input torque	N·m	
	ImpSpd	Impeller rotational shaft speed	rad/s	
Turb	TurbTrq	Applied turbine torque	N·m	
	TurbSpd	Turbine rotational shaft speed	rad/s	
Cltch	CltchForce	Applied clutch force	N	
	CltchLocked	Clutch locked or unlocked state	N/A	
TrqConv	TrqConvSpdRatio	Turbine to impeller speed ratio	N/A	
	TrqConvEta	Torque conversion efficiency	N/A	
PwrInfo	PwrTrnsfrd	PwrImp	Applied impeller power	W
		PwrTurb	Applied turbine output power	W
	PwrNotTrnsfrd	PwrDampLoss	Mechanical damping loss	W
		PwrFluidCplingLoss	Heat loss to transmission fluid	W
		PwrCltchLoss	Clutch slip power loss	W
	PwrStored	PwrStoredImp	Rate change in impeller rotational kinetic energy	W
PwrStoredTurb		Rate change in turbine rotational kinetic energy	W	

ImpSpd – Impeller speed

scalar

Impeller rotational shaft speed, ω_i , in rad/s.

TrbSpd — Turbine speed

scalar

Turbine rotational shaft speed, ω_t , in rad/s.**Parameters****Configuration****Lock-up clutch configuration — Select lock-up clutch configuration**

Lock-up (default) | No lock-up | External lock-up input

To Model	Select
Fluid-coupling only	No lock-up
Automatic clutch engagement	Lock-up
Clutch pressure as input from an external signal	External lock-up input

Dependencies

To enable the **Clutch** parameters, select Lock-up or External lock-up input for the **Lock-up clutch configuration** parameter.

Torque Converter**Impeller shaft inertia, Ji — Inertia**

.1 (default) | scalar

Impeller shaft inertia, in $\text{kg}\cdot\text{m}^2$.**Impeller shaft viscous damping, bi — Viscous damping coefficient**

.001 (default) | scalar

Impeller shaft viscous damping, in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.**Turbine shaft inertia, Jt — Inertia**

.1 (default) | scalar

Turbine shaft inertia, in $\text{kg}\cdot\text{m}^2$.**Turbine shaft viscous damping, bt — Viscous damping coefficient**

.001 (default) | scalar

Turbine shaft viscous damping, in $\text{N}\cdot\text{m}\cdot\text{s}/\text{rad}$.**Initial impeller shaft velocity, omegai_o — Angular velocity**

0 (default) | scalar

Initial impeller shaft velocity, in rad/s.

Initial turbine shaft velocity, omegat_o — Angular velocity

0 (default) | scalar

Initial turbine shaft velocity, in rad/s.

Speed ratio vector, phi – Ratio

[0 0.50 0.60 0.70 0.80 0.87 0.92 0.94 0.96 0.97] (default) | vector

Vector of turbine speed to impeller speed ratios. Breakpoints for the capacity and torque multiplication vectors.

Capacity factor parameterization – Select factor ratio type

Input speed / sqrt(input torque) (default) | Absorbed torque / input speed^2

To Set Factor Ratio to	Select
Impeller angular velocity to square root impeller torque	Input speed / sqrt(input torque)
Impeller absorbed torque to square of impeller angular velocity	Absorbed torque / input speed^2

Capacity vector, psi – Vector

[12.2938 12.8588 13.1452 13.6285 14.6163 16.2675 19.3503 22.1046 29.9986 50.00] (default) | vector

Capacity factor parameterization Setting	Capacity Vector Units
Input speed / sqrt(input torque)	(rad/s)/(N·m)^0.5
Absorbed torque / input speed^2	N·m/(rad/s)^2

Torque ratio vector, zeta – Vector

[2.2320 1.5462 1.4058 1.2746 1.1528 1.0732 1.0192 0.9983 0.9983 0.9983] (default) | vector

Vector of turbine torque to impeller speed ratios.

Fluid torque response time constant (set to 0 to disable), tauTC – Time constant

.02 (default) | scalar

To account for the delay in torque calculations due to changing input torque, specify the fluid torque transfer time constant, in s.

Interpolation method – Select interpolation method

Linear (default) | Flat | Nearest

Interpolates the torque ratio and capacity factor functions between the discrete relative velocity values.

Clutch

Clutch force equivalent net radius, R_{eff} – Effective radius

.3 (default) | scalar

The effective radius, R_{eff} , used with the applied clutch friction force to determine the friction force, in m. The effective radius is defined as:

$$R_{eff} = \frac{2(R_o^3 - R_i^3)}{3(R_o^2 - R_i^2)}$$

The equation uses these variables.

R_o Annular disk outer radius

R_i Annular disk inner radius

Dependencies

To enable the **Clutch** parameters, select Lock-up or External lock-up input for the **Lock-up clutch configuration** parameter.

Static friction coefficient, μ_s – Coefficient

1.2 (default) | scalar

Dimensionless clutch disc coefficient of static friction.

Dependencies

To enable the **Clutch** parameters, select Lock-up or External lock-up input for the **Lock-up clutch configuration** parameter.

Kinetic friction coefficient, μ_k – Coefficient

1 (default) | scalar

Dimensionless clutch disc coefficient of kinetic friction.

To enable the **Clutch** parameters, select Lock-up or External lock-up input for the **Lock-up clutch configuration** parameter.

Initially lock clutch – Select to initially lock clutch

off (default) | on

Dependencies

To enable this parameter, select Lock-up or External lock-up input for the **Lock-up clutch configuration** parameter.

Lock-up speed ratio threshold, ϕ_{lu} – Threshold

.85 (default) | scalar

Set speed ratio threshold that engages clutch lock-up.

Dependencies

To enable this parameter, select Lock-up for the **Lock-up clutch configuration** parameter.

Minimum lock-up engagement speed, ω_{gl} – Angular velocity

$900 \cdot \pi / 30$ (default) | scalar

Set the minimum impeller speed that engages clutch lock-up, in rad/s.

Dependencies

To enable this parameter, select Lock-up for the **Lock-up clutch configuration** parameter.

Lock-up disengagement speed, ω_{gd} – Angular velocity

$800 \cdot \pi / 30$ (default) | scalar

Set the minimum impeller speed that disengages clutch lock-up, in rad/s.

Dependencies

To enable this parameter, select Lock-up for the **Lock-up clutch configuration** parameter.

Lock-up clutch force gain, K_c – Gain

5000 (default) | scalar

Open loop clutch lock-up force gain, in N.

Dependencies

To enable this parameter, select Lock-up for the **Lock-up clutch configuration** parameter.

Lock-up clutch time constant, τ_C – Time constant

.0500 (default) | scalar

Open loop clutch lock-up time constant, in s.

Dependencies

To enable this parameter, select Lock-up for the **Lock-up clutch configuration** parameter.

Version History

Introduced in R2017a

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

See Also

CI Core Engine | SI Core Engine

Functions

mdf

Access information contained in MDF-file

Syntax

```
mdfObj = mdf(mdfFileName)
```

Description

The `mdf` function creates an object for accessing a measurement data format (MDF) file. See “Measurement Data Format (MDF)” on page 8-4.

`mdfObj = mdf(mdfFileName)` identifies a measurement data format (MDF) file and returns an MDF-file object, which you can use to access information and data contained in the file. You can specify a full or partial path to the file.

Examples

Create an MDF-File Object for a Specified MDF-File

Create an MDF object for a given file, and view the object display.

```
mdfObj = mdf([matlabroot, '/examples/vnt/data/Logging_MDF.mf4'])
```

```
mdfObj =
```

```
    MDF with properties:
```

```
    File Details
```

```
        Name: 'Logging_MDF.mf4'
        Path: 'C:\Program Files\MATLAB\R2021b\examples\vnt\data\Logging_MDF.mf4'
        Author: ''
    Department: ''
        Project: ''
        Subject: ''
        Comment: ''
        Version: '4.10'
        DataSize: 1542223
    InitialTimestamp: 2020-06-25 20:41:13.133000000
```

```
    Creator Details
```

```
        ProgramIdentifier: 'MDF4Lib'
        Creator: [1x1 struct]
```

```
    File Contents
```

```
        Attachment: [5x1 struct]
    ChannelNames: {62x1 cell}
    ChannelGroup: [1x62 struct]
```

Options

Conversion: Numeric

Input Arguments

mdfFileName — MDF-file name

char vector | string

MDF-file name, specified as a character vector or string, including the necessary full or relative path.

Example: 'MDFFile.mf4'

Data Types: char | string

Output Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, returned as an MDF-file object. The object provides access to the MDF-file information contained in the following properties.

Property	Description
Name	Name of the MDF-file, including extension
Path	Full path to the MDF-file, including file name
Author	Author who originated the MDF-file
Department	Department that originated the MDF-file
Project	Project that originated the MDF-file
Subject	Subject matter in the MDF-file
Comment	Open comment field from the MDF-file
Version	MDF standard version of the file
DataSize	Total size of the data in the MDF-file, in bytes
InitialTimestamp	Time when file data acquisition began in UTC or local time
ProgramIdentifier	Originating program of the MDF-file
Creator	Structure containing details about creator of the MDF-file, with these fields: VendorName, ToolName, ToolVersion, UserName, and Comment
Attachment	Structure of information about attachments contained within the MDF-file, with these fields: Name, Path, Comment, Type, MIMEType, Size, EmbeddedSize, and MD5Checksum
ChannelNames	Cell array of the channel names in each channel group
ChannelGroup	Structure of information about channel groups contained within the MDF-file, with these fields: AcquisitionName, Comment, NumSamples, DataSize, Sorted, SourceInfo, and Channel

Property	Description
Conversion	Conversion option for data in the MDF-file. Supported values are: <ul style="list-style-type: none">'Numeric' (default) — Apply only numeric conversion rules (CC_Type 1-6). Data with non-numeric conversion rules is imported as raw, unconverted values.'None' — Do not apply any conversion rules. All data is imported as raw data.'All' — Apply all numeric and text conversion rules (CC_Type 1-10).

More About

Measurement Data Format (MDF)

Measurement data format (MDF) files are binary format files for storing measurement data. The format standard is defined by the Association for Standardization of Automation and Measuring Systems (ASAM), which you can read about at ASAM MDF.

Vehicle Network Toolbox™ and Powertrain Blockset provide access to MDF-files through an object you create with the `mdf` function.

Version History

Introduced in R2016b

See Also

Functions

`saveAttachment` | `read`

read

Package: asam

Read channel data from MDF-file

Syntax

```
data = read(mdfObj)
data = read(mdfObj, chanList)
data = read(mdfObj, chanGroupIndex)
data = read(mdfObj, chanGroupIndex, chanName)
data = read(mdfObj, chanGroupIndex, chanName, startPosition)
data = read(mdfObj, chanGroupIndex, chanName, startPosition, endPosition)
data = read( ____, Name=Value)
[data, time] = read( ____, OutputFormat="Vector")
```

Description

`data = read(mdfObj)` reads all data for all channels from the MDF-file identified by the MDF-file object `mdfObj`, and assigns the output to `data`. If the file data is one channel group, the output is a timetable; multiple channel groups are returned as a cell array of timetables, where the cell array index corresponds to the channel group number.

`data = read(mdfObj, chanList)` reads data for all channels specified in the channel list table `chanList`.

`data = read(mdfObj, chanGroupIndex)` reads data for all channels in the specified channel group.

`data = read(mdfObj, chanGroupIndex, chanName)` reads data for the specified channels.

`data = read(mdfObj, chanGroupIndex, chanName, startPosition)` reads data from the position specified by `startPosition`.

`data = read(mdfObj, chanGroupIndex, chanName, startPosition, endPosition)` reads data for the range specified from `startPosition` to `endPosition`.

`data = read(____, Name=Value)` specifies certain function behaviors using optional name-value pairs.

`[data, time] = read(____, OutputFormat="Vector")` returns two vectors: one vector of channel data and a corresponding vector of timestamps. This form of syntax with two output arguments is supported only when `OutputFormat="Vector"`.

Examples

Read All Data from MDF-File

Read all available data from the MDF-file.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj);
```

Read Raw Data

Read raw data from a specified channel in the first channel group, without applying any conversion rules.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj,1,"Unsigned_UInt32_LE_Primary_Offset_0",Conversion="None");
data(1:4,:)
```

```
ans =
```

```
4×1 timetable
```

Time	Unsigned_UInt32_LE_Primary_Offset_0
0 sec	0
1 sec	1
2 sec	2
3 sec	3

Read All Data from Specified Channel List

Read all available data from the MDF-file for channels specified as part of a channel list.

```
mdfObj = mdf("MDFFile.mf4");
chanList = channelList(mdfObj) % Channel table
data = read(mdfObj,chanList(1:3,:)); % First 3 channels
```

Read All Data from Multiple Channels

Read all available data from the MDF-file for specified channels.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj,1,["Channel1","Channel2"]);
```

Read Range of Data from Specified Index Values

Read a range of data from the MDF-file using indexing for startPosition and endPosition to specify the data range.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj,1,["Channel1","Channel2"],1,10);
```


Read Range of Data from Specified Time Values

Read a range of data from the MDF-file using time values for `startPosition` and `endPosition` to specify the data range.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj,1,["Channel1","Channel2"],seconds(5.5),seconds(7.3));
```

Read All Data in Vector Format

Read all available data from the MDF-file, returning data and time vectors.

```
mdfObj = mdf("MDFFile.mf4");
[data,time] = read(mdfObj,1,"Channel1",OutputFormat="Vector");
```

Read All Data in Time Series Format

Read all available data from the MDF-file, returning time series data.

```
mdfObj = mdf("MDFFile.mf4");
data = read(mdfObj,1,"Channel1",OutputFormat="TimeSeries");
```

Read Data from Channel List Entry

Read data from a channel identified by the `channelList` function.

Get list of channels and display their names and group numbers.

```
mdfObj = mdf("File05.mf4");
chlist = channelList(mdfObj);
chlist(1:2,1:2) % Partial listing
```

2×2 table

ChannelName	ChannelGroupNumber
"Float_32_LE_Offset_64"	2
"Float_64_LE_Primary_Offset_0"	2

Read data from the first channel in the list.

```
data = read(mdfObj,chlist{1,2},chlist{1,1});
data(1:5,:)
```

5×1 timetable

Time	Float_32_LE_Offset_64
0 sec	5
0.01 sec	5.1
0.02 sec	5.2

```
0.03 sec      5.3
0.04 sec      5.4
```

Read Data and Metadata

Read data from an MDF-file into a timetable, along with channel group and channel metadata.

Read from channel group 1 into a timetable.

```
mdfObj = mdf("File05.mf4");
Ttout = read(mdfObj,1,IncludeMetadata=true);
Ttout.Properties.CustomProperties
```

```
ans =
```

```
CustomProperties with properties:
```

```
ChannelGroupAcquisitionName: ""
ChannelGroupComment: "Integer Types"
ChannelGroupSourceInfo: [1x1 struct]
ChannelDisplayName: ["" ""]
ChannelComment: ["" ""]
ChannelUnit: ["" ""]
ChannelType: [FixedLength FixedLength]
ChannelDataType: [IntegerSignedLittleEndian IntegerUnsignedLittleEndian]
ChannelNumBits: [16 32]
ChannelComponentType: [None None]
ChannelCompositionType: [None None]
ChannelSourceInfo: [1x2 struct]
ChannelReadOption: [Numeric Numeric]
```

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf("MDFFile.mf4")`

chanList — List of channels

table

List of channels, specified as a table in the format returned by the `channelList` function.

Example: `channelList()`

Data Types: table

chanGroupIndex — Index of the channel group

numeric value

Index of channel group, specified as a numeric value that identifies the channel group from which to read.

Example: 1

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

chanName — Name of channel

string | char vector

Name of channel, specified as a string, character vector, or array. `chanName` identifies the name of a channel in the channel group. Use a cell array of character vectors or array of strings to identify multiple channels.

Example: "Channel1"

Data Types: `char` | `string` | `cell`

startPosition — First position of channel data

numeric value | duration

First position of channel data, specified as a numeric value or duration. The `startPosition` option specifies the first position from which to read channel data. Provide a numeric value to specify an index position; use a duration to specify a time position. If only `startPosition` is provided without the `endPosition` option, the data value at that location is returned. When used with `endPosition` to specify a range, the function returns data from the `startPosition` (inclusive) to the `endPosition` (noninclusive).

Example: 1

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `duration`

endPosition — Last position of channel data range

numeric value | duration

Last position of channel data range, specified as a numeric value or duration. The `endPosition` option specifies the last position for reading a range of channel data. Provide both the `startPosition` and `endPosition` to specify retrieval of a range of data. The function returns up to but not including `endPosition` when reading a range. Provide a numeric value to specify an index position; use a duration to specify a time position.

Example: 1000

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `duration`

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, ..., NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose `Name` in quotes.

Example: `Conversion="Numeric"`

OutputFormat — Format for output data

"Timetable" (default) | "Vector" | "TimeSeries"

Format for output data, specified as a string or character vector. This option formats the output according to the following table.

OutputFormat	Description
"Timetable"	Return a timetable from one or more channels into one output variable. This is the only format allowed when reading from multiple channels at the same time. (Default.) Note: The timetable format includes variables for the MDF channels. Because the variable titles must be valid MATLAB identifiers, they might not be exactly the same as those values in the MDF object ChannelNames property. The variable headers are derived from the property using the function <code>matlab.lang.makeValidName</code> . The original channel names are available in the VariableDescriptions property of the timetable object.
"Vector"	Return a vector of numeric data values, and optionally a vector of time values from one channel. Use one output variable to return only data, or two output variables to return vectors for both data and time stamps.
"TimeSeries"	Return a time series of data from one channel.

Example: "Vector"

Data Types: char | string

Conversion — Conversion option for MDF-file data

"Numeric" (default) | "All" | "None"

Conversion option for MDF-file data, specified as "Numeric", "All", or "None". The default uses the value specified in the Conversion property of the mdf object. This option overrides that setting.

- "Numeric" — Apply only numeric conversion rules (CC_Type 1-6). Data with non-numeric conversion rules are imported as raw, unconverted values.
- "None" — Do not apply any conversion rules. All data are imported as raw data.
- "All" — Apply all numeric and text conversion rules (CC_Type 1-10).

Example: Conversion="All"

Data Types: char | string

IncludeMetadata — Read metadata with data

false (default) | true

Read channel group and channel metadata from the MDF-file along with its data. The default value is false. Metadata can only be included when the OutputFormat is specified as "Timetable". The timetable cannot be empty. You can access the metadata in `data.Properties.CustomProperties`.

Specifying IncludeMetadata=true might impact function performance when reading data from a channel group with many channels.

Example: IncludeMetadata=true

Data Types: logical

Output Arguments

data — Channel data

timetable (default) | double | time series | cell array

Channel data, returned as a timetable, cell array of timetables, vector of doubles, or a time series according to the `OutputFormat` option value and the number of channel groups.

time — Channel data times

double

Channel data times, returned as a vector of double elements. The time vector is returned only when `OutputFormat="Vector"`.

Version History

Introduced in R2016b

See Also

Functions

`mdf` | `saveAttachment` | `channelList` | `mdfWrite` | `mdfAddChannelGroupMetadata`

Topics

“Time Series”

“Represent Dates and Times in MATLAB”

“Tables”

saveAttachment

Package: asam

Save attachment from MDF-file

Syntax

```
saveAttachment(mdfObj, AttachmentName)  
saveAttachment(mdfObj, AttachmentName, DestFile)
```

Description

`saveAttachment(mdfObj, AttachmentName)` saves the specified attachment from the MDF-file to the current MATLAB working folder. The attachment is saved with its existing name.

`saveAttachment(mdfObj, AttachmentName, DestFile)` saves the specified attachment from the MDF-file to the given destination. You can specify relative or absolute paths to place the attachment in a specific folder.

Examples

Save Attachment with Original Name

Save an MDF-file attachment with its original name in the current folder.

```
mdfObj = mdf('MDFFile.mf4');  
saveAttachment(mdfObj, 'AttachmentName.ext')
```

Save Attachment with New Name

Save an MDF-file attachment with a new name in the current folder.

```
mdfObj = mdf('MDFFile.mf4');  
saveAttachment(mdfObj, 'AttachmentName.ext', 'MyFile.ext')
```

Save Attachment in Parent Folder

Save an MDF-file attachment in a folder specified with a relative path name, in this case in the parent of the current folder.

```
mdfObj = mdf('MDFFile.mf4');  
saveAttachment(mdfObj, 'AttachmentName.ext', '..\MyFile.ext')
```

Save Attachment in Specified Folder

This example saves an MDF-file attachment using an absolute path name.

```
mdfObj = mdf('MDFFile.mf4');  
saveAttachment(mdfObj, 'AttachmentName.ext', 'C:\MyDir\MyFile.ext')
```

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf('MDFFile.mf4')`

AttachmentName — MDF-file attachment name

char vector | string

MDF-file attachment name, specified as a character vector or string. The name of the attachment is available in the `Name` field of the MDF-file object `Attachment` property.

Example: `'file1.dbc'`

Data Types: char | string

DestFile — Destination file name for the saved attachment

existing attachment name (default) | char vector | string

Destination file name for the saved attachment, specified as a character vector or string. The specified destination can include an absolute or relative path, otherwise the attachment is saved in the current folder.

Example: `'MyFile.ext'`

Data Types: char | string

Version History

Introduced in R2016b

See Also

Functions

`mdf` | `read`

mdfDatastore

Datastore for collection of MDF-files

Description

Use the MDF datastore object to access data from a collection of MDF-files.

Creation

Syntax

```
mdfds = mdfDatastore(location)
mdfds = mdfDatastore(__, 'Name1', Value1, 'Name2', Value2, ...)
```

Description

`mdfds = mdfDatastore(location)` creates an `MDFDatastore` based on an MDF-file or a collection of files in the folder specified by `location`. All files in the folder with extensions `.mdf`, `.dat`, or `.mf4` are included.

`mdfds = mdfDatastore(__, 'Name1', Value1, 'Name2', Value2, ...)` specifies function options and properties of `mdfds` using optional name-value pairs.

Input Arguments

location — Location of MDF datastore files

character vector | cell array | `DsFileSet` object

Location of MDF datastore files, specified as a character vector, cell array of character vectors, or `matlab.io.datastore.DsFileSet` object identifying either files or folders. The path can be relative or absolute, and can contain the wildcard character `*`. If `location` specifies a folder, by default the datastore includes all files in that folder with the extensions `.mdf`, `.dat`, or `.mf4`.

Example: `'CANape.MF4'`

Data Types: `char` | `cell` | `DsFileSet`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments to set file information or object “Properties” on page 8-15. Allowed options are `IncludeSubfolders`, `FileExtensions`, and the properties `ReadSize`, `SelectedChannelGroupNumber`, and `SelectedChannelNames`.

Example: `'SelectedChannelNames', 'Counter_B4'`

IncludeSubfolders — Include files in subfolders

`false` (default) | `true`

Include files in subfolders, specified as a logical. Specify `true` to include files in each folder and recursively in subfolders.

Example: `'IncludeSubfolders',true`

Data Types: `logical`

FileExtensions — Custom extensions for filenames to include in MDF datastore

`{'.mdf','.dat','.mf4'}` (default) | `char` | `cell`

Custom extensions for filenames to include in the MDF datastore, specified as a character vector or cell array of character vectors. By default, the supported extensions include `.mdf`, `.dat`, and `.mf4`. If your files have custom or nonstandard extensions, use this Name-Value setting to include files with those extensions.

Example: `'FileExtensions',{'myformat1','myformat2'}`

Data Types: `char` | `cell`

Properties

ChannelGroups — All channel groups present in first MDF-file

`table`

This property is read-only.

All channel groups present in first MDF-file, returned as a table.

Data Types: `table`

Channels — All channels present in first MDF-file

`table`

This property is read-only.

All channels present in first MDF-file, returned as a table.

Those channels targeted for reading must have the same name and belong to the same channel group in each file of the MDF datastore.

Data Types: `table`

Files — Files included in datastore

`char` | `string` | `cell`

Files included in the datastore, specified as a character vector, string, or cell array.

Example: `{'file1.mf4','file2.mf4'}`

Data Types: `char` | `string` | `cell`

ReadSize — Size of data returned by read

`'file'` (default) | `numeric` | `duration`

Size of data returned by the `read` function, specified as `'file'`, a numeric value, or a duration. A character vector value of `'file'` causes the entire file to be read; a numeric double value specifies the number of records to read; and a duration value specifies a time range to read.

If you later change the `ReadSize` property value type, the datastore resets.

Example: `50`

Data Types: double | char | duration

SelectedChannelGroupNumber — Channel group to read

numeric scalar

Channel group to read, specified as a numeric scalar value.

Example: 1

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

SelectedChannelNames — Names of channels to read

char | string | cell

Names of channels to read, specified as a character vector, string, or cell array.

Those channels targeted for reading must have the same name and belong to the same channel group in each file of the MDF datastore.

Example: 'Counter_B4'

Data Types: char | string | cell

Conversion — Conversion option for MDF-file data

'Numeric' (default) | 'All' | 'None'

Conversion option for MDF-file data, specified as 'Numeric', 'All', or 'None'.

- 'Numeric' (default) — Apply only numeric conversion rules (CC_Type 1-6). Data with non-numeric conversion rules is imported as raw, unconverted values.
- 'None' — Do not apply any conversion rules. All data is imported as raw data.
- 'All' — Apply all numeric and text conversion rules (CC_Type 1-10).

Example: 'All'

Data Types: char | string

Object Functions

read	Read data in MDF datastore
readall	Read all data in MDF datastore
preview	Subset of data from MDF datastore
reset	Reset MDF datastore to initial state
hasdata	Determine if data is available to read from MDF datastore
partition	Partition MDF datastore
numpartitions	Number of partitions for MDF datastore
combine (MATLAB)	Combine data from multiple datastores
transform (MATLAB)	Transform datastore
isPartitionable (MATLAB)	Determine whether datastore is partitionable
isShuffleable (MATLAB)	Determine whether datastore is shuffleable

Examples

Create an MDF Datastore

Create an MDF datastore from the sample file `CANape.MF4`, and read it into a timetable.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'data', 'CANape.MF4'));  
while hasdata(mdfds)  
    m = read(mdfds);  
end
```

Version History

Introduced in R2017b

See Also

hasdata

Package: matlab.io.datastore

Determine if data is available to read from MDF datastore

Syntax

```
tf = hasdata(mdfds)
```

Description

`tf = hasdata(mdfds)` returns logical 1 (true) if there is data available to read from the MDF datastore specified by `mdfds`. Otherwise, it returns logical 0 (false).

Examples

Check MDF Datastore for Readable Data

Use `hasdata` in a loop to control read iterations.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'data', 'CANape.MF4'));  
while hasdata(mdfds)  
    m = read(mdfds);  
end
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

tf — Indicator of data to read

1 | 0

Indicator of data to read, returned as a logical 1 (true) or 0 (false).

Version History

Introduced in R2017b

See Also

Functions

mdfDatastore | read | readall | reset

numpartitions

Package: matlab.io.datastore

Number of partitions for MDF datastore

Syntax

```
N = numpartitions(mdfds)
N = numpartitions(mdfds,pool)
```

Description

`N = numpartitions(mdfds)` returns the recommended number of partitions for the MDF datastore `mdfds`. Use the result as an input to the `partition` function.

`N = numpartitions(mdfds,pool)` returns a reasonable number of partitions to parallelize `mdfds` over the parallel pool, `pool`, based on the number of files in the datastore and the number of workers in the pool.

Examples

Find Recommended Number of Partitions for MDF Datastore

Determine the number of partitions you should use for your MDF datastore.

```
mdfds = mdfDatastore(fullfile(matlabroot,'examples','vnt','data','CANape.MF4'));
N = numpartitions(mdfds);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

pool — Parallel pool

parallel pool object

Parallel pool specified as a parallel pool object.

Example: `gcp`

Output Arguments

N — Number of partitions

double

Number of partitions, returned as a double. This number is the calculated recommendation for the number of partitions for your MDF datastore. Use this when partitioning your datastore with the `partition` function.

Version History

Introduced in R2017b

See Also

Functions

`mdfDatastore` | `read` | `reset` | `partition`

partition

Package: matlab.io.datastore

Partition MDF datastore

Syntax

```
subds = partition(mdfds,N,index)
subds = partition(mdfds,'Files',index)
subds = partition(mdfds,'Files',filename)
```

Description

`subds = partition(mdfds,N,index)` partitions the MDF datastore `mdfds` into the number of parts specified by `N`, and returns the partition corresponding to the index `index`.

`subds = partition(mdfds,'Files',index)` partitions the MDF datastore by files and returns the partition corresponding to the file of index `index` in the `Files` property.

`subds = partition(mdfds,'Files',filename)` partitions the datastore by files and returns the partition corresponding to the specified filename.

Examples

Partition an MDF Datastore into Default Parts

Partition an MDF datastore from the sample file `CANape.MF4`, and return the first part.

```
mdfds = mdfDatastore(fullfile(matlabroot,'examples','vnt','data','CANape.MF4'));
N = numpartitions(mdfds);
subds1 = partition(mdfds,N,1);
```

Partition an MDF Datastore by Its Files

Partition an MDF datastore according to its files, and return partitions by index and file name.

```
cd c:\temp
mdfds = mdfDatastore({'CANape1.MF4','CANape2.MF4','CANape3.MF4'});
mdfds.Files

ans =
    3×1 cell array
    'c:\temp\CANape1.MF4'
    'c:\temp\CANape2.MF4'
    'c:\temp\CANape3.MF4'
```



```
subds2 = partition(mdfds,'files',2);  
subds3 = partition(mdfds,'files','c:\temp\CANape3.MF4');
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

N — Number of partitions

positive integer

Number of partitions, specified as a double of positive integer value. Use the `numpartitions` function for the recommended number of partitions.

Example: `numpartitions(mdfds)`

Data Types: double

index — Index

positive integer

Index, specified as a double of positive integer value. When using the 'files' partition scheme, this value corresponds to the index of the MDF datastore object `Files` property.

Example: 1

Data Types: double

filename — File name

character vector

File name, specified as a character vector. The argument can specify a relative or absolute path.

Example: `'CANape.MF4'`

Data Types: char

Output Arguments

subds — MDF datastore partition

MDF datastore object

MDF datastore partition, returned as an MDF datastore object. This output datastore is of the same type as the input datastore `mdfds`.

Version History

Introduced in R2017b

See Also

Functions

mdfDatastore | read | reset | numpartitions

preview

Package: matlab.io.datastore

Subset of data from MDF datastore

Syntax

```
data = preview(mdfds)
```

Description

`data = preview(mdfds)` returns a subset of data from MDF datastore `mdfds` without changing the current position in the datastore.

Examples

Examine Preview of MDF Datastore

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'data', 'CANape.MF4'));
data = preview(mdfds)
```

```
data2 =
```

```
10x74 timetable
```

	Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM
	0.00082554 sec	0	0	1	0	100
	0.010826 sec	0	0	1	0	100
	0.020826 sec	0	0	1	0	100
	0.030826 sec	0	0	1	0	100
	0.040826 sec	0	0	1	0	100
	0.050826 sec	0	0	1	0	100
	0.060826 sec	0	0	1	0	100
	0.070826 sec	0	0	1	0	100

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Subset of data

timetable

Subset of data, returned as a timetable of MDF records.

Version History

Introduced in R2017b

See Also

Functions

mdfDatastore | read | hasdata

read

Package: matlab.io.datastore

Read data in MDF datastore

Syntax

```
data = read(mdfds)
[data,info] = read(mdfds)
```

Description

`data = read(mdfds)` reads data from the MDF datastore specified by `mdfds`, and returns a timetable.

The `read` function returns a subset of data from the datastore. The size of the subset is determined by the `ReadSize` property of the datastore object. On the first call, `read` starts reading from the beginning of the datastore, and subsequent calls continue reading from the endpoint of the previous call. Use `reset` to read from the beginning again.

`[data,info] = read(mdfds)` also returns to the output argument `info` information, including metadata, about the extracted data.

Examples

Read Datastore by Files

Read data from an MDF datastore one file at a time.

```
mdfds = mdfDatastore({'CANape1.MF4','CANape2.MF4','CANape3.MF4'});
mdfds.ReadSize = 'file';
data = read(mdfds);
```

Read the second file and view information about the data.

```
[data2,info2] = read(mdfds);
info2

    struct with fields:
        Filename: 'CANape2.MF4'
        FileSize: 57592
        MDFFileProperties: [1x1 struct]
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Output data

timetable

Output data, returned as a timetable of MDF records.

info — Information about data

structure array

Information about data, returned as a structure array with the following fields:

Filename

FileSize

MDFFileProperties

Version History

Introduced in R2017b

See Also

Functions

`mdfDatastore` | `readall` | `preview` | `reset` | `hasdata`

readall

Package: matlab.io.datastore

Read all data in MDF datastore

Syntax

```
data = readall(mdfds)
data = readall(mdfds,"UseParallel",true)
```

Description

`data = readall(mdfds)` reads all the data in the MDF datastore specified by `mdfds`, and returns a timetable.

After the `readall` function returns all the data, it resets `mdfds` to point to the beginning of the datastore.

If all the data in the datastore does not fit in memory, then `readall` returns an error.

`data = readall(mdfds,"UseParallel",true)` specifies to use a parallel pool to read all of the data. By default, the "UseParallel" option is `false`. The choice of pool depends on the following conditions:

- If you already have a parallel pool running, that pool is used.
- If your parallel preference settings allow a pool to automatically start, this syntax will start one, using the default cluster.
- If no pool is running and one cannot automatically start, this syntax does not use parallel functionality.

Examples

Read All Data in Datastore

Read all the data from a multiple file MDF datastore into a timetable.

```
mdfds = mdfDatastore({'CANape1.MF4','CANape2.MF4','CANape3.MF4'});
data = readall(mdfds);
```

Read All Data in Datastore

Use a parallel pool to read all the data from the datastore into a timetable.

```
mdfds = mdfDatastore({'CANape1.MF4', 'CANape2.MF4', 'CANape3.MF4'});  
data = readall(mdfds, "UseParallel", true);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Output data

timetable

Output data, returned as a timetable of MDF records.

Version History

Introduced in R2017b

See Also

Functions

`mdfDatastore` | `read` | `preview` | `reset` | `hasdata`

reset

Package: matlab.io.datastore

Reset MDF datastore to initial state

Syntax

```
reset(mdfds)
```

Description

`reset(mdfds)` resets the MDF datastore specified by `mdfds` to its initial read state, where no data has been read from it. Resetting allows you to reread from the same datastore.

Examples

Reset MDF Datastore

Reset an MDF datastore so that you can read from it again.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'data', 'CANape.MF4'));  
data = read(mdfds);  
reset(mdfds);  
data = read(mdfds);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Version History

Introduced in R2017b

See Also

Functions

`mdfDatastore` | `read` | `hasdata`

channelList

Package: asam

Information on available MDF groups and channels

Syntax

```
chans = channelList(mdfobj)
channelList(mdfobj, chanName)
channelList(mdfobj, chanName, 'ExactMatch', true)
```

Description

`chans = channelList(mdfobj)` returns a table of information about channels and groups in the specified MDF-file.

`channelList(mdfobj, chanName)` searches the MDF-file to generate a list of channels matching the specified channel name. The search by default is case-insensitive and identifies partial matches. A table is returned containing information about the matched channels and the containing channel groups. If no matches are found, an empty table is returned.

`channelList(mdfobj, chanName, 'ExactMatch', true)` searches the channels for an exact match, including case sensitivity. This is useful if a channel name is a substring of other channel names.

Examples

View Available MDF Channels

View all available MDF channels.

```
mdfObj = mdf('File01.mf4');
chans = channelList(mdfObj)
```

chans =

4×9 table

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples
"Float_32_LE_Offset_64"	2	10000
"Float_64_LE_Primary_Offset_0"	2	10000
"Signed_Int16_LE_Offset_32"	1	10000
"Unsigned_UInt32_LE_Primary_Offset_0"	1	10000

View Specific MDF Channels

Filter on channel names.

```
chans = channelList(mdfObj, 'Float')
```

```

chans =
  2×9 table
      ChannelName      ChannelGroupNumber      ChannelGroupNumSamples
      -----
      "Float_32_LE_Offset_64"      2      10000
      "Float_64_LE_Primary_Offset_0"      2      10000

chans = channelList(mdfObj, 'Float', 'ExactMatch', true)

chans =
  0×9 empty table

```

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf('File01.mf4')`

chanName — Name of channel

char vector | string

Name of channel, specified as a character vector or string. By default, case-insensitive and partial matches are returned.

Example: `'Channel1'`

Data Types: char | string

Output Arguments

chans — Information on available MDF channels

table

Information on available MDF channels, returned as a table. To access specific elements, you can index into the table.

Version History

Introduced in R2018b

See Also

Functions

`mdf`

mdfVisualize

View channel data from MDF-file

Syntax

```
mdfVisualize(mdfFileName)
```

Description

`mdfVisualize(mdfFileName)` opens an MDF-file in the Simulation Data Inspector for viewing and interacting with channel data. `mdfFileName` is the name of the MDF-file, specified as a full or partial path.

Note `mdfVisualize` supports only integer and floating point data types in MDF-file channels.

Examples

View MDF Data

View the data from a specified MDF-file in the Simulation Data Inspector.

```
mdfVisualize('File01.mf4')
```

Input Arguments

mdfFileName — MDF-file name

char vector | string

MDF-file name, specified as a character vector or string, including the necessary full or relative path.

Example: 'MDFFile.mf4'

Data Types: char | string

Version History

Introduced in R2019a

See Also

Functions

mdf | read

Topics

“View and Analyze Simulation Results”

autoblks.pwr.PlantInfo

Analyze powertrain power and energy

Description

To assess powertrain efficiencies, use the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level reference applications.

Creation

Syntax

```
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName)
```

Description

MATLAB creates an `autoblks.pwr.PlantInfo` object for the system that you specify. `VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName)` where `SysName` is the name of the model or subsystem that you want to analyze.

Input Arguments

SysName — Model name

character vector

Model that you want to analyze.

Example: `'SiCiPtReferenceApplication'`

Data Types: `char`

Properties

AvgEff — Average efficiency

double

This property is read-only.

Average efficiency, dimensionless.

Eff — Time series of efficiency

time series

This property is read-only.

Efficiency, η , dimensionless. To calculate the efficiency, the `Eff` property implements this equation.

$$\eta = \left| \frac{\sum P_{output} - \sum P_{store}(P_{store} > 0)}{\sum P_{input} - \sum P_{store}(P_{store} < 0)} \right|$$

The equation uses these variables.

P_{store}	Stored power
P_{input}, P_{output}	Input and output power logged by Power Accounting Bus Creator block

EnergyBalanceAbsTol – Energy balance absolute tolerance

0.0100 (default)

Energy balance absolute tolerance, $EnergyBal_{AbsTol}$.

To determine if the system conserves energy, the `isEnergyBalanced` method checks the energy conservation at each time step.

$$E_{Err} = \sum E_{trans} + \sum E_{nottrans} - \sum E_{store}$$

Blocks change the input energy plus released stored energy to output energy plus stored energy. For example, a mapped engine block uses fuel (not transferred energy) to produce torque (transferred energy) and heat loss (not transferred energy). The total modified energy represents the average between the input fuel energy and the energy exiting the system (torque and heat loss). To calculate the total energy modified by the block, the method uses the integral of the average transferred, not transferred, and stored power.

$$E_{total} = \frac{1}{2} \left(\int_0^{t_{end}} \left(\sum |P_{trans}| + \sum |P_{nottrans}| + \sum |P_{store}| \right) dt \right) \Bigg|_{t=t_{end}}$$

If the energy conservation error is within an error tolerance, the method returns true. Specifically, if either condition is met, the method returns true.

Condition		
$\frac{ E_{Err} }{E_{total}} < EnergyBal_{RelTol}$	or	$E_{total} < EnergyBal_{AbsTol}$

The equations use these variables.

E_{Err}	Energy conservation error
E_{total}	Total energy modified by block
$EnergyBal_{RelTol}, EnergyBal_{AbsTol}$	Energy balance relative and absolute tolerance, respectively
P_{trans}, E_{trans}	Transferred power and energy, respectively
$P_{nottrans}, E_{nottrans}$	Not transferred power and energy, respectively

P_{store}, E_{store} Stored power and energy, respectively
 P_{input}, P_{output} Input and output power logged by Power Accounting Bus Creator block

Data Types: double

EnergyBalanceRelTol – Energy balance relative tolerance

0.0100 (default)

Energy balance relative tolerance, $EnergyBal_{RelTol}$.

To determine if the system conserves energy, the `isEnergyBalanced` method checks the energy conservation at each time step.

$$E_{Err} = \sum E_{trans} + \sum E_{nottrans} - \sum E_{store}$$

Blocks change the input energy plus released stored energy to output energy plus stored energy. For example, a mapped engine block uses fuel (not transferred energy) to produce torque (transferred energy) and heat loss (not transferred energy). The total modified energy represents the average between the input fuel energy and the energy exiting the system (torque and heat loss). To calculate the total energy modified by the block, the method uses the integral of the average transferred, not transferred, and stored power.

$$E_{total} = \frac{1}{2} \left(\int_0^{t_{end}} \left(\sum |P_{trans}| + \sum |P_{nottrans}| + \sum |P_{store}| \right) dt \right) \Bigg|_{t=t_{end}}$$

If the energy conservation error is within an error tolerance, the method returns true. Specifically, if either condition is met, the method returns true.

Condition		
$\frac{ E_{Err} }{E_{total}} < EnergyBal_{RelTol}$	or	$E_{total} < EnergyBal_{AbsTol}$

The equations use these variables.

E_{Err} Energy conservation error
 E_{total} Total energy modified by block
 $EnergyBal_{RelTol}, EnergyBal_{AbsTol}$ Energy balance relative and absolute tolerance, respectively
 P_{trans}, E_{trans} Transferred power and energy, respectively
 $P_{nottrans}, E_{nottrans}$ Not transferred power and energy, respectively
 P_{store}, E_{store} Stored power and energy, respectively
 P_{input}, P_{output} Input and output power logged by Power Accounting Bus Creator block

Data Types: double

EnrgyUnits — Energy units

MJ (default) | J

Energy units.

Example: `VehPwrAnalysis.EnrgyUnits = 'MJ';`

Data Types: char

PwrUnits — Power units

kW (default) | W

Power units.

Example: `VehPwrAnalysis.PwrUnits = 'kW';`

Data Types: char

Object Methods

<code>addLoggedData</code>	Add logged data
<code>dispSignalSummary</code>	Display powertrain subsystem energy analysis
<code>dispSysSummary</code>	Display powertrain system efficiency
<code>findChildSys</code>	Powertrain subsystem energy analysis
<code>histogramEff</code>	Display powertrain subsystem efficiency histogram
<code>isEnrgyBalanced</code>	Logical flag for energy conservation
<code>loggingOff</code>	Turn signal logging off
<code>loggingOn</code>	Turn signal logging on
<code>run</code>	Run powertrain energy and power analysis
<code>sdiSummary</code>	Display Simulation Data Inspector plots of powertrain energy and power
<code>xlsSysSummary</code>	Write powertrain energy analysis to spreadsheet

Examples**Create PlantInfo Object for Powertrain Energy Analysis**

Analyze the power and energy in the conventional vehicle reference application. To create a `PlantInfo` object, see “step 2” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);
VehPwrAnalysis.PwrUnits = 'kW';
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.


```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis, EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis, DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis, {EngSysName, DrvtrnSysName})
```

Version History

Introduced in R2019a

See Also

Power Accounting Bus Creator

Topics

“Conventional Vehicle Powertrain Efficiency”

“Analyze Power and Energy”

dispSignalSummary

Display powertrain subsystem energy analysis

Syntax

```
dispSignalSummary(SubSystem)
```

Description

The `dispSignalSummary(SubSystem)` method displays the subsystem energy for the `autoblks.pwr.PlantInfo` object. Use the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

After you use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the subsystem that you want to analyze, use the `dispSignalSummary(SubSystem)` method to display the results.

Examples

Use dispSignalSummary Method to Display Subsystem Results

Analyze the power and energy in the conventional vehicle reference application. To use the `dispSignalSummary` method to display the engine and drivetrain subsystem results, see “step 6” on page 8-0 and “step 7” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

SubSystem — Subsystem name

character vector

Subsystem that you want to analyze.

Example: 'SiCiPtReferenceApplication/Passenger Car/Engine'

Example: 'SiCiPtReferenceApplication/Passenger Car/Drivetrain'

Data Types: char

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

dispSysSummary

Display powertrain system efficiency

Syntax

```
dispSysSummary(PlantInfoObj)
```

Description

After you use the `run` method to analyze the powertrain power and energy, use the `dispSysSummary(PlantInfoObj)` method to display the system efficiency for the `autoblks.pwr.PlantInfo` object.

Use instances of the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

Examples

Use dispSysSummary Method to Display Energy Analysis Results

Analyze the power and energy in the conventional vehicle reference application. To use the `dispSysSummary` method to display the results, see “step 4” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

findChildSys

Powertrain subsystem energy analysis

Syntax

```
findChildSys(PlantInfoObj, SubSystem)
```

Description

The `findChildSys(PlantInfoObj, SubSystem)` method finds and returns an `autoblks.pwr.PlantInfo` object for the subsystem. Use the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level reference applications.

After you use the `run` method to analyze the powertrain power and energy, use the `findChildSys` method to evaluate specific subsystems.

Examples

Use findChildSys Method to Analyze Subsystems

Analyze the power and energy in the conventional vehicle reference application. To use the `findChildSys` method to analyze the engine and drivetrain subsystems, see “step 6” on page 8-0 and “step 7” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

SubSystem — Subsystem name

character vector

Subsystem that you want to analyze.

Example: 'SiCiPtReferenceApplication/Passenger Car/Engine'

Example: 'SiCiPtReferenceApplication/Passenger Car/Drivetrain'

Data Types: char

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

histogramEff

Display powertrain subsystem efficiency histogram

Syntax

```
histogramEff(SubSystem)
```

Description

The `histogramEff(SubSystem)` method displays a histogram of the powertrain subsystem efficiency for the `autoblks.pwr.PlantInfo` object. Use instances of the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

After you use the `findChildSys` method to analyze the powertrain subsystem power and energy, use the `histogramEff` method to display a histogram of the efficiency.

Examples

Use histogramEff Method to Display Results

Analyze the power and energy in the conventional vehicle reference application. To use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency, see “step 6” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```


Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

SubSystem — Subsystem name

character vector

Subsystem that you want to analyze.

Example: 'SiCiPtReferenceApplication/Passenger Car/Engine'

Example: 'SiCiPtReferenceApplication/Passenger Car/Drivetrain'

Data Types: char

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

run

Run powertrain energy and power analysis

Syntax

```
run(PlantInfoObj)
```

Description

Use the `run(PlantInfoObj)` method to turn signal logging on, run a powertrain energy and power analysis, and add data to the `autoblks.pwr.PlantInfo` object. Use instances of the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

Examples

Use run Method for Powertrain Energy Analysis

Analyze the power and energy in the conventional vehicle reference application. To use the `run` method for the analysis, see “step 3” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

sdiSummary

Display Simulation Data Inspector plots of powertrain energy and power

Syntax

```
sdiSummary(PlantInfoObj,blocknames)
```

Description

The `sdiSummary(PlantInfoObj,blocknames)` method plots the powertrain energy and power analysis results for the `autoblks.pwr.PlantInfo` object.

Use instances of the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

Examples

Use sdiSummary Method to Plot Results

Analyze the power and energy in the conventional vehicle reference application. To use the `sdiSummary` method to display the Simulation Data Inspector plots of the engine and drivetrain results, see “step 8” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';  
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);  
VehPwrAnalysis.PwrUnits = 'kW';  
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis,'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

blocknames — Block or name

character vector | string | 'all'

Block or subsystem names, specified as a character vector or a string, separated by a comma.

Example: 'SiCiPtReferenceApplication/Passenger Car/Engine'

Example: 'SiCiPtReferenceApplication/Passenger Car/Engine', 'SiCiPtReferenceApplication/Passenger Car/Drivetrain'

Data Types: char | string

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”
Simulation Data Inspector

xlsSysSummary

Write powertrain energy analysis to spreadsheet

Syntax

```
xlsSysSummary(PlantInfoObj, filename, sheet)
```

Description

The `xlsSysSummary(PlantInfoObj, filename, sheet)` method exports the system energy and efficiency for the `autoblks.pwr.PlantInfo` object. Use the `autoblks.pwr.PlantInfo` object to evaluate and report power and energy for component-level blocks and system-level models.

After you use the `run` method to analyze the powertrain power and energy, use the `xlsSysSummary` method to write the results to a spreadsheet.

Examples

Use xlsSysSummary Method to Write Results to Spreadsheet

Analyze the power and energy in the conventional vehicle reference application. To use the `xlsSysSummary` method to write the results to a spreadsheet, see “step 5” on page 8-0 .

Open the conventional vehicle reference application. By default, the application has a mapped 1.5 L spark-ignition (SI) engine and a dual clutch transmission. Project files open in a writable location.

```
autoblkConVehStart
```

Set the system name to `SiCiPtReferenceApplication`.

Create the `autoblks.pwr.PlantInfo` object.

Use the `PwrUnits` and `EnrgyUnits` properties to specify the units.

```
SysName = 'SiCiPtReferenceApplication';
VehPwrAnalysis = autoblks.pwr.PlantInfo(SysName);
VehPwrAnalysis.PwrUnits = 'kW';
VehPwrAnalysis.EnrgyUnits = 'MJ';
```

Use the `run` method to turn on logging, run simulation, and add logged data to the object.

```
run(VehPwrAnalysis);
```

Use the `dispSysSummary` method to display the results.

```
dispSysSummary(VehPwrAnalysis);
```

Use the `xlsSysSummary` method to write the results to a spreadsheet.

```
xlsSysSummary(VehPwrAnalysis, 'EnergySummary.xlsx');
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Engine subsystem.

To display the results, use the `dispSignalSummary` method.

Use the `histogramEff` method to display a histogram of the time spent at each engine plant efficiency.

```
EngSysName = 'SiCiPtReferenceApplication/Passenger Car/Engine';
EngPwrAnalysis = findChildSys(VehPwrAnalysis,EngSysName);
dispSignalSummary(EngPwrAnalysis);
histogramEff(EngPwrAnalysis);
```

Use the `findChildSys` method to retrieve the `autoblks.pwr.PlantInfo` object for the Drivetrain subsystem.

To display the results, use the `dispSignalSummary` method.

```
DrvtrnSysName = 'SiCiPtReferenceApplication/Passenger Car/Drivetrain';
DrvtrnPwrAnalysis = findChildSys(VehPwrAnalysis,DrvtrnSysName);
dispSignalSummary(DrvtrnPwrAnalysis);
```

To plot the results, use the `sdiSummary` method.

```
sdiSummary(VehPwrAnalysis,{EngSysName,DrvtrnSysName})
```

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

filename — File name

character vector | string

File name, specified as a character vector or a string.

If `filename` does not exist, `xlsSysSummary` creates a file, determining the format based on the specified extension. To create a file compatible with Excel® 97-2003 software, specify an extension of `.xls`. To create files in Excel 2007 formats, specify an extension of `.xlsx`, `.xlsb`, or `.xlsm`. If you do not specify an extension, `xlsSysSummary` uses the default, `.xls`.

Example: 'myFile.xlsx' or "myFile.xlsx"

Example: 'C:\myFolder\myFile.xlsx'

Example: 'myFile.csv'

Data Types: char | string

sheet — Worksheet name

character vector | string | positive integer

Worksheet name, specified as one of the following:

- Character vector or string that contains the worksheet name. The name cannot contain a colon (:). To determine the names of the sheets in a spreadsheet file, use `xlsinfo`.

- Positive integer that indicates the worksheet index.

If `sheet` does not exist, `xlswrite` adds a sheet at the end of the worksheet collection. If `sheet` is an index larger than the number of worksheets, `xlswrite` appends empty sheets until the number of worksheets in the workbook equals `sheet`. In either case, `xlswrite` generates a warning indicating that it has added a worksheet.

Data Types: `char` | `string` | `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

Version History

Introduced in R2019a

See Also

`autoblks.pwr.PlantInfo` | `xlswrite`

Topics

“Analyze Power and Energy”

addLoggedData

Add logged data

Syntax

```
addLoggedData(PlantInfoObj,logout)
```

Description

`addLoggedData(PlantInfoObj,logout)` adds logged signal data to the `autoblks.pwr.PlantInfo` object specified by the `Simulink.SimulationData.Dataset` signal data object.

If the data logged for the system does not conserve energy, the method returns a warning.

If the `Simulink.SimulationData.Dataset` object does not include data for the Power Accounting Bus Creator blocks in the system, the method returns an error.

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

logout — Dataset object for signals

`Simulink.SimulationData.Dataset` object

`Simulink.SimulationData.Dataset` object for signals that you want to log.

Version History

Introduced in R2019a

See Also

Power Accounting Bus Creator | `autoblks.pwr.PlantInfo`

Topics

"Analyze Power and Energy"

isEnergyBalanced

Logical flag for energy conservation

Syntax

```
flag=isEnergyBalanced(PlantInfoObj)
```

Description

`flag=isEnergyBalanced(PlantInfoObj)` returns logical 1 (true) if the system conserves energy. Otherwise, it returns logical 0 (false).

Input Arguments

PlantInfoObj — Instance of PlantInfo object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

Output Arguments

flag — Indicator of energy conservation

1 (true) | 0 (false)

Indicator of energy conservation, returned as a logical 1 (true) or 0 (false).

Data Types: `logical`

Algorithms

To determine if the system conserves energy, the `isEnergyBalanced` method checks the energy conservation at each time step.

$$E_{Err} = \sum E_{trans} + \sum E_{nottrans} - \sum E_{store}$$

Blocks change the input energy plus released stored energy to output energy plus stored energy. For example, a mapped engine block uses fuel (not transferred energy) to produce torque (transferred energy) and heat loss (not transferred energy). The total modified energy represents the average between the input fuel energy and the energy exiting the system (torque and heat loss). To calculate the total energy modified by the block, the method uses the integral of the average transferred, not transferred, and stored power.

$$E_{total} = \frac{1}{2} \left(\int_0^{t_{end}} \left(\sum |P_{trans}| + \sum |P_{nottrans}| + \sum |P_{store}| \right) dt \right) \Bigg|_{t=t_{end}}$$

If the energy conservation error is within an error tolerance, the method returns true. Specifically, if either condition is met, the method returns true.

Condition		
$\frac{ E_{Err} }{E_{total}} < EnergyBal_{RelTol}$	or	$E_{total} < EnergyBal_{AbsTol}$

The equations use these variables.

E_{Err}	Energy conservation error
E_{total}	Total energy modified by block
$EnergyBal_{RelTol}, EnergyBal_{AbsTol}$	Energy balance relative and absolute tolerance, respectively
P_{trans}, E_{trans}	Transferred power and energy, respectively
$P_{nottrans}, E_{nottrans}$	Not transferred power and energy, respectively
P_{store}, E_{store}	Stored power and energy, respectively
P_{input}, P_{output}	Input and output power logged by Power Accounting Bus Creator block

Version History

Introduced in R2019a

See Also

Power Accounting Bus Creator | `autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

loggingOff

Turn signal logging off

Syntax

```
loggingOff(PlantInfoObj)
```

Description

`loggingOff(PlantInfoObj)` turns signal logging off for all Power Accounting Bus Creator blocks in the `autoblks.pwr.PlantInfo` system object.

Input Arguments

PlantInfoObj — Instance of PlantInfo object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

Version History

Introduced in R2019a

See Also

Power Accounting Bus Creator | `autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

loggingOn

Turn signal logging on

Syntax

```
loggingOn(PlantInfoObj)
```

Description

`loggingOn(PlantInfoObj)` turns signal logging on for all Power Accounting Bus Creator blocks in the `autoblks.pwr.PlantInfo` system object.

Input Arguments

PlantInfoObj — Instance of **PlantInfo** object

`autoblks.pwr.PlantInfo` object

`autoblks.pwr.PlantInfo` object for the system that you want to analyze.

Version History

Introduced in R2019a

See Also

Power Accounting Bus Creator | `autoblks.pwr.PlantInfo`

Topics

“Analyze Power and Energy”

Battery.PulseSequence

Define a single pulse sequence

Description

Use the `Battery.PulseSequence` object to define a single experimental pulse sequence at a specific temperature and pulse current magnitude.

You can place multiple experimental pulse sequences into an array of `Battery.PulseSequence` objects. To do so, create a `Battery.PulseSequence` object for each experimental pulse sequence instance.

To use the `Battery.PulseSequence` object and methods, you need these products:

- Powertrain Blockset
- Curve Fitting Toolbox™
- Optimization Toolbox™
- Parallel Computing Toolbox™
- Simulink Design Optimization

Creation

Syntax

```
psObj = Battery.PulseSequence
```

Description

MATLAB creates a `psObj = Battery.PulseSequence` object that defines a pulse sequence.

Properties

Data — Raw data

m-by-5 array

An m-by-5 array of pulse sequence data. Use the `addData` object function to add the data. `addData` computes the charge and state of charge (SOC), using the assumption that the experimental test ranges is 0% to 100% SOC.

Array Element	Description	Unit
<code>Data(m,1)</code>	Time	s
<code>Data(m,2)</code>	Voltage	V
<code>Data(m,3)</code>	Current	A
<code>Data(m,4)</code>	Charge	A·s

Array Element	Description	Unit
Data(m,5)	State of charge (SOC)	Dimensionless

Data Types: double

ModelName — Name of model

character vector

Name of the model to use for simulation

Example: 'BatteryEstim3RC_PTBS'

Data Types: char

MetaData — Battery.MetaData object properties

0-by-1 array

Battery.MetaData object properties containing metadata for the data.

Data Types: function_handle

Capacity — Pulse sequence capacity

scalar

Capacity observed as the difference between lowest and highest energy, in A.s. Calculated by the `addData` method, but can be overwritten.

Example: 0.0

Data Types: double

Parameters — Battery.Parameters object properties

0-by-1 array

Battery.Parameters object containing the most recently determined battery equivalent circuit parameters.

Data Types: function_handle

ParametersHistory — Battery.ParametersHistory object properties

0-by-1 array

Battery.ParametersHistory object array containing the history of the battery equivalent circuit parameters through different estimation steps. The last element is the most recent parameter set.

Data Types: function_handle

Object Functions

<code>addData</code>	Import pulse sequence experimental data
<code>createPulses</code>	Identify pulses and create pulse objects from experimental data
<code>estimateInitialEmR0</code>	Estimate open circuit voltage and series resistance
<code>estimateInitialEmRx</code>	Estimate open circuit voltage and RC pair resistance
<code>estimateInitialTau</code>	Estimate RC pair time constant
<code>estimateParameters</code>	Estimate parameters
<code>getSocIdxForPulses</code>	Return state of charge index for pulses
<code>loadDataFromMatFile</code>	Load pulse data from a MAT-file

<code>plot</code>	Plot pulse sequence data
<code>plotIdentifiedPulses</code>	Plot identified pulses
<code>plotLatestParameters</code>	Plot latest pulse sequence parameters
<code>plotSimulationResults</code>	Plot pulse sequence simulation results
<code>populatePulseParameters</code>	Populate pulse parameters
<code>removePulses</code>	Remove pulses from sequence
<code>repairTimeVector</code>	Repair time vector

Examples

Add File Data to Battery.PulseSequence Object

This example shows how to add data to a `Battery.PulseSequence` object.

Create a pulse sequence object.

```
psObj = Battery.PulseSequence;  
disp(psObj)
```

Load data from a file.

```
FileName = 'Synthetic_LiPo_PulseDischarge.mat';  
[time,voltage,current] = Battery.loadDataFromMatFile(FileName);
```

Add the data to the pulse sequence.

```
addData(psObj,time,voltage,current);
```

Version History

Introduced in R2016b

See Also

`Battery.Metadata` | `Battery.Parameters` | `Battery.Pulse` | `sdo.OptimizeOptions`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

addData

Import pulse sequence experimental data

Syntax

```
addData(psObj,Time,Voltage,Current)
```

Description

`addData(psObj,Time,Voltage,Current)` adds the pulse sequence experimental data to the `Battery.PulseSequence` object. The `Time`, `Voltage`, and `Current` input arrays must have equal lengths. `addData` computes the charge and state of charge (SOC), using the assumption that the experimental test range is 0% to 100% SOC.

Examples

Add Data to Battery.PulseSequence Object

This example shows how to add data to a `Battery.PulseSequence` object.

Create a pulse sequence object.

```
psObj = Battery.PulseSequence;  
disp(psObj)
```

Load data from a file.

```
FileName = 'Synthetic_LiPo_PulseDischarge.mat';  
[time,voltage,current] = Battery.loadDataFromMatFile(FileName);
```

Add the data to the pulse sequence.

```
addData(psObj,time,voltage,current);
```

Input Arguments

psObj — Instance of Battery.PulseSequence class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Time — Time

m-by-1 array

m-by-1 array of time data, in s.

Data Types: double

Voltage — Voltage

m-by-1 array

m-by-1 array of voltage data, in V.

Data Types: double

Current — Current

m-by-1 array

m-by-1 array of current data, in A.

Data Types: double

Version History

Introduced in R2016b

See Also

Battery.PulseSequence

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

loadDataFromMatFile

Load pulse data from a MAT-file

Syntax

```
[Time,Voltage,Current] = loadDataFromMatFile(FileName)
[Time,Voltage,Current] = loadDataFromMatFile(FileName,Name,Value)
```

Description

`[Time,Voltage,Current] = loadDataFromMatFile(FileName)` function loads pulse data from a MAT-file.

`[Time,Voltage,Current] = loadDataFromMatFile(FileName,Name,Value)` function loads pulse data from a MAT-file with additional options specified by one or more `Name, Value` pair arguments.

Examples

Load File Data to Battery.PulseSequence Object

This example shows how to add data to a `Battery.PulseSequence` object.

Create a pulse sequence object.

```
psObj = Battery.PulseSequence;
disp(psObj);
```

Load data from a file.

```
FileName = 'Synthetic_LiPo_PulseDischarge.mat';
[time,voltage,current] = Battery.loadDataFromMatFile(FileName);
```

Add the data to the pulse sequence.

```
addData(psObj,time,voltage,current);
```

Input Arguments

FileName — Path or file name

`untitled.mat` (default) | path, or MAT-file name

Path or file name of the MAT-file that contains the pulse sequence data.

Example: `'Synthetic_LiPo_PulseDischarge.mat'`

Data Types: `char`

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, . . . , NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose `Name` in quotes.

Example: `Battery.loadDataFromMatFile(FileName, 'TimeVariable', 'myTimeVariable')`

TimeVariable — Time variable in MAT-file

`time` (default) | character vector

Use this value to specify the time variable to search for in the MAT-file. If unspecified, the method searches for variables containing `'time'`.

Example: `Battery.loadDataFromMatFile(FileName, 'TimeVariable', 'myTimeVariable')`

Data Types: char

VoltageVariable — Voltage variable in MAT-file

`volt` (default) | character vector

Use this value to specify the voltage variable to search for in the MAT-file. If unspecified, the method searches for variables containing `'voltage'`.

Example:

`Battery.loadDataFromMatFile(FileName, 'VoltageVariable', 'myVoltageVariable')`

Data Types: char

CurrentVariable — Current variable in MAT-file

`current` (default) | character vector

Use this value to specify the current variable to search for in the MAT-file. If unspecified, the method searches for variables containing `'current'`.

Example:

`Battery.loadDataFromMatFile(FileName, 'CurrentVariable', 'myCurrentVariable')`

Data Types: char

Output Arguments

Time — Time

m-by-1 array

m-by-1 array of time data, in s.

Data Types: double

Voltage — Voltage

m-by-1 array

m-by-1 array of voltage data, in V.

Data Types: double

Current — Current

m-by-1 array

m-by-1 array of current data, in A.

Data Types: double

Version History

Introduced in R2016b

See Also

Battery.PulseSequence

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

createPulses

Identify pulses and create pulse objects from experimental data

Syntax

```
createPulses(psObj)
createPulses(psObj, Name, Value)
```

Description

`createPulses(psObj)` identifies the location of pulse events. Creates separate pulse objects from the `Battery.PulseSequence` object experimental data.

`createPulses(psObj, Name, Value)` identifies the location of pulse events. Creates separate pulse objects from the `Battery.PulseSequence` object experimental data with additional options specified by one or more `Name, Value` pair arguments.

Examples

Create Pulse Objects from Data

This example shows how to create pulse objects from data.

Create a pulse sequence object.

```
psObj = Battery.PulseSequence;
disp(psObj)
```

Load data from a file.

```
FileName = 'Synthetic_LiPo_PulseDischarge.mat';
[time,voltage,current] = Battery.loadDataFromMatFile(FileName);
```

Add the data to the pulse sequence.

```
addData(psObj,time,voltage,current);
```

Create pulse objects from data.

```
createPulses(psObj,...
    'CurrentOnThreshold',0.1,...
    'NumRCBranches',3,...
    'RCBranchesUse2TimeConstants',false,...
    'PreBufferSamples',10,...
    'PostBufferSamples',15);
```

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

Battery.PulseSequence object for the pulse sequence that you want to analyze.

Name-Value Pair Arguments

Specify optional pairs of arguments as Name1=Value1, . . . , NameN=ValueN, where Name is the argument name and Value is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose Name in quotes.

Example: `createPulses(psObj, 'CurrentOnThreshold', 0.1)`

CurrentOnThreshold — Minimum current magnitude

0.025 (default) | scalar

Use this value to specify the minimum current magnitude for identifying the pulse locations, in A. The `createPulses` function considers values below the `CurrentOnThreshold` as relaxation or measurement noise.

Example: `createPulses(psObj, 'CurrentOnThreshold', 0.1)`

Data Types: double

NumRCBranches — Number of RC branches

3 (default) | scalar

Use this value to specify the number of RC branches. To change the number of branches after an estimation, you must rerun `createPulses` along with any estimation steps. Rerunning ensures that the estimation parameters are the right size.

Example: `createPulses(psObj, 'NumRCBranches', 4)`

Data Types: uint32

RCBranchesUse2TimeConstants — Use load and relaxation time constants

false

The `createPulses` function does not support using separate time constants for load and relaxation when it estimates each RC branch. If you set the value to true, the `createPulses` function might produce an error.

Example: `createPulses(psObj, 'RCBranchesUse2TimeConstants', false)`

Data Types: logical

PreBufferSamples — Data samples to retain before pulse estimation

10 (default) | scalar

Use this value to specify the number of data samples to retain before pulse estimation. The buffer allows the estimation to focus on matching the measured data before the pulse begins.

Example: `createPulses(psObj, 'PreBufferSamples', 5)`

Data Types: uint32

PostBufferSamples — Data samples to retain for next estimation

15 (default) | scalar

Use this value to specify the number of samples to retain before the next pulse estimation. The buffer allows the estimation to focus on matching the transition when the next pulse begins. Typically, the

end transition of one pulse and the starting transition at the next pulse are at the same state of charge (SOC). Therefore, both transitions help determine the parameter values at that SOC breakpoint.

Example: `createPulses(psObj, 'PostBufferSamples', 14)`

Data Types: `uint32`

PulseRequires2Samples – Pulse requires two consecutive samples under current

`false` (default)

Use this value to specify that there must be two consecutive samples under current to define a pulse. Set to `true` if occasional noise spikes in the current measurement trigger a false pulse detection. By default, the value is `false`, indicating that a single sample above the threshold detects a pulse event.

Example: `createPulses(psObj, 'PulseRequires2Samples', true)`

Data Types: `logical`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

estimateInitialEmR0

Estimate open circuit voltage and series resistance

Syntax

```
estimateInitialEmR0(psObj)
estimateInitialEmR0(psObj,Name,Value)
```

Description

`estimateInitialEmR0(psObj)` estimates the open circuit voltage, E_m , and series resistance, R_o , for the `Battery.PulseSequence` object data. For the estimation, the method uses data points around each pulse transition. The method uses estimated values to determine the minimum and maximum constraint values. The method stores the results in an `Battery.Parameters` object.

`estimateInitialEmR0(psObj,Name,Value)` estimates the open circuit voltage, E_m , and series resistance, R_o , for the `Battery.PulseSequence` object data with additional options specified by one or more `Name,Value` pair arguments.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, . . . ,NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose Name in quotes.

Example:

```
estimateInitialEmR0(psObj,'SetEmConstraints',false,'EstimateEm',true,'EstimateR0',true)
```

SetEmConstraints — Use open circuit voltage constraints

`true` (default)

Use this value to specify if the method constrains the open circuit voltage, E_o , to within maximum or minimum values. To determine the maximum and minimum voltage, the method uses the voltage at the end of relaxation as a constraint for future estimation steps.

If the pulse is a discharge pulse, the voltage rises during relaxation. The final relaxation voltage is set to the minimum constraint for E_o at the corresponding state of charge (SOC).

If the pulse is a charge pulse, the voltage falls during relaxation. The final relaxation voltage is set to the maximum constraint at the corresponding SOC.

Example: `estimateInitialEmR0(psObj, 'SetEmConstraints', false)`

Data Types: `logical`

EstimateEm – Estimate open circuit voltage

`true` (default) | `false`

Use this value to specify if the method estimates the open circuit voltage, E_m . Use the default setting, `true`, unless you have already defined the E_m values from outside analysis.

Example: `eestimateInitialEmR0(psObj, 'EstimateEm', false)`

Data Types: `logical`

EstimateR0 – Estimate series resistance

`true` (default) | `false`

Use this value to specify if the method estimates the series resistance, R_0 . Use the default setting, `true`, unless you have already defined the R_0 values from outside analysis.

Example: `estimateInitialEmR0(psObj, 'EstimateR0', false)`

Data Types: `logical`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

estimateInitialEmRx

Estimate open circuit voltage and RC pair resistance

Syntax

```
estimateInitialEmRx(psObj)
estimateInitialEmRx(psObj,Name,Value)
```

Description

`estimateInitialEmRx(psObj)` estimates the open circuit voltage, Em , and RC pair resistance, Ex , for the `Battery.PulseSequence` object data. For the estimation, the method solves a linear system of equations throughout the pulse sequence. The method stores the results in a `Battery.Parameters` object.

`estimateInitialEmRx(psObj,Name,Value)` estimates the open circuit voltage, Em , and RC pair resistance, Ex , for the `Battery.PulseSequence` object data with additional options specified by one or more `Name,Value` pair arguments.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, ..., NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose `Name` in quotes.

Example:

```
estimateInitialEmRx(psObj,'IgnoreRelaxation',false,'ShowPlots',true,'ShowBeforePlots',true,'PlotDelay',0.5,'EstimateEm',true)
```

EstimateEm — Estimate voltage

true (default) | false

Use this value to specify if the method estimates the open circuit voltage, Em .

Example: `estimateInitialEmRx(psObj,'EstimateEm',false)`

Data Types: logical

RetainEm — Retain voltage estimate

true (default) | false

Use this value to specify if the method retains the open circuit voltage, E_m , estimate. Set to `true` if you want the method to use an external open circuit voltage to state of charge (SOC) relationship. If `EstimateEm` is `false`, this option does not apply.

Example: `estimateInitialEmRx(psObj, 'RetainEm', false)`

Data Types: `logical`

EstimateR0 — Estimate series resistance

`true` (default) | `false`

Use this value to specify if the method estimates the series resistance, R_o .

Example: `estimateInitialEmRx(psObj, 'EstimateR0', false)`

Data Types: `logical`

RetainR0 — Retain series resistance

`true` (default) | `false`

Use this value to specify if the method retains the identified series resistance, R_o , estimate. Set to `true` if you want the method to use an existing series resistance to state of charge (SOC) relationship. If `EstimateEm` is `false`, this option does not apply.

Example: `estimateInitialEmRx(psObj, 'RetainR0', false)`

Data Types: `logical`

ShowPlots — Show estimation plots

`false` (default) | `true`

Use this value to specify if the method shows plots during each estimation step.

Example: `estimateInitialEmRx(psObj, 'ShowPlots', true)`

Data Types: `logical`

ShowBeforePlots — Show before estimation plots

`false` (default) | `true`

Use this value to specify if the method shows before plots during each estimation step. If `ShowPlots` is `false`, this option does not apply.

Example: `estimateInitialEmRx(psObj, 'ShowBeforePlots', true)`

Data Types: `logical`

PlotDelay — Plot delay

`0.0` (default) | `scalar`

Use this value to specify the time delay after showing the plots, in s.

Example: `estimateInitialEmRx(psObj, 'PlotDelay', 0.1)`

Data Types: `double`

IgnoreRelaxation — Estimate series resistance

`false` (default) | `true`

Use this value to specify if the method completely ignores the relaxation and fits only the main pulse.

Example: `estimateInitialEmRx(psObj, 'IgnoreRelaxation', true)`

Data Types: `logical`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

estimateInitialTau

Estimate RC pair time constant

Syntax

```
estimateInitialTau(psObj)
estimateInitialTau(psObj, Name, Value)
```

Description

`estimateInitialTau(psObj)` estimates the RC pair time constant, *Tau* for the `Battery.PulseSequence` object data. For the estimation, the method fits the relaxation curve for each pulse. The method stores the results in an `Battery.Parameters` object.

`estimateInitialTau(psObj, Name, Value)` estimates the RC pair time constant, *Tau* for the `Battery.PulseSequence` object data with additional options specified by one or more `Name, Value` pair arguments.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, ..., NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose Name in quotes.

Example:

```
estimateInitialTau(psObj, 'UpdateEndingEm', false, 'ShowPlots', true, 'ReusePlotFigure', true, 'UseLoadData', false, 'PlotDelay', 0.5)
```

ShowPlots — Show estimation plots

false (default) | true

Use this value to specify if the method shows plots during each estimation step.

Example: `estimateInitialTau(psObj, 'ShowPlots', true)`

Data Types: logical

PlotDelay — Plot delay

0.0 (default) | scalar

Use this value to specify the time delay after showing the plots, in s.

Example: `estimateInitialTau(psObj, 'PlotDelay', 0.5)`

Data Types: double

ReusePlotFigure — Reuse plots

true (default) | false

Use this value to specify if the method reuses the same plot figure. If `false`, the estimation plots are in separate figure windows. If `ShowPlots` is `false`, the option does not apply.

Example: `estimateInitialTau(psObj, 'ReusePlotFigure', true)`

Data Types: logical

UpdateEndingEm — Update voltage estimate

false (default) | true

Use this value to specify if the method updates the open circuit voltage estimate at the end of the relaxation, based on the curve fits.

Example: `estimateInitialTau(psObj, 'UpdateEndingEm', true)`

Data Types: logical

UseLoadData — Plot delay

false (default) | true

Use this value to specify if the method uses the pulse load data, instead of pulse relaxation data, to estimate the time constant, *Tau*. By default, the setting is `false`, and the method uses the pulse relaxation to estimate the time constant.

Example: `estimateInitialTau(psObj, 'UseLoadData', true)`

Data Types: logical

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

estimateParameters

Estimate parameters

Syntax

```
estimateParameters(psObj)
estimateParameters(psObj,Name,Value)
```

Description

`estimateParameters(psObj)` estimates the parameters in the `Battery.Parameters` object. The method stores the results in an `Battery.Parameters` object.

`estimateParameters(psObj,Name,Value)` estimates the parameters in the `Battery.Parameters` object data with additional options specified by one or more `Name,Value` pair arguments.

To use the `Battery.PulseSequence` object and methods, you need these products:

- Powertrain Blockset
- Curve Fitting Toolbox
- Optimization Toolbox
- Parallel Computing Toolbox
- Simulink Design Optimization

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Name-Value Pair Arguments

Specify optional pairs of arguments as `Name1=Value1, ..., NameN=ValueN`, where `Name` is the argument name and `Value` is the corresponding value. Name-value arguments must appear after other arguments, but the order of the pairs does not matter.

Before R2021a, use commas to separate each name and value, and enclose Name in quotes.

Example:

```
estimateParameters(psObj, 'CarryParamToNextPulse', true, 'ShowPlots', true, 'EstimateEm', true, 'RetainEm', true, 'EstimateR0', true, 'RetainR0', true)
```

CarryParamsToNextPulse — Use results for next SOC

`false` (default) | `true`

Use this value to specify if the method uses the identified current pulse final state of charge (SOC) parameter values as the initial estimate for the parameter values at the next SOC.

Example: `estimateParameters(psObj, 'CarryParamsToNextPulse', true)`

Data Types: `logical`

EstimateEm — Estimate voltage

`true` (default) | `false`

Use this value to specify if the method estimates the open circuit voltage, E_m .

Example: `estimateParameters(psObj, 'EstimateEm', false)`

Data Types: `logical`

RetainEm — Retain voltage estimate

`true` (default) | `false`

Use this value to specify if the method retains the identified open circuit voltage, E_m , estimate. If `EstimateEm` is `false`, this option does to apply.

Example: `estimateParameters(psObj, 'RetainEm', false)`

Data Types: `logical`

EstimateR0 — Estimate series resistance

`true` (default) | `false`

Use this value to specify if the method estimates the series resistance, R_0 .

Example: `estimateParameters(psObj, 'EstimateR0', false)`

Data Types: `logical`

RetainR0 — Retain series resistance

`true` (default) | `false`

Use this value to specify if the method retains the series resistance, R_0 , estimate. If `EstimateR0` is `false`, this option does to apply.

Example: `estimateParameters(psObj, 'RetainR0', false)`

Data Types: `logical`

SD0OptimizeOptions — Specify optimization options

'Method' is `lsqnonlin` and 'UseParallel' is `true` (default)

Use this value to specify the `sdo.OptimizeOptions` object options. For example:

```
SD0OptimizeOptions = sdo.OptimizeOptions(...
    'OptimizedModel', psObj.ModelName, ...
    'Method', 'lsqnonlin', ...
    'UseParallel', 'always')
```

ShowPlots — Show estimation plots

`false` (default) | `true`

Use this value to specify if the method shows plots during each estimation step.

Example: `estimateParameters(psObj, 'ShowPlots', true)`

Data Types: `logical`

ReusePlotFigure — Reuse plots`true (default) | false`

Use this value to specify if the method reuses the same plot figure. If `false`, the estimation plots are in separate figure windows. If `ShowPlots` is `false`, the option does not apply.

Example: `estimateParameters(psObj, 'ReusePlotFigure', true)`

Data Types: `logical`

PlotDelay — Plot delay`5.0 (default) | scalar`

Use this value to specify the time delay after showing the plots, in s.

Example: `estimateParameters(psObj, 'PlotDelay', 0.1)`

Data Types: `double`

PulseNumbers — Pulse numbers`1 (default) | scalar`

Use this value to specify the pulse numbers to estimate. The default value, 1, is set to estimate all the pulses.

Data Types: `uint32`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence` | `sdo.OptimizeOptions`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

getSocIdxForPulses

Return state of charge index for pulses

Syntax

```
idx=getSocIdxForPulses(psObj,pulseList)
```

Description

`idx=getSocIdxForPulses(psObj,pulseList)` returns the row vector index of the state of charge (SOC) lookup table breakpoints.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

pulseList — Index of pulses

`1:NumPulses` (default)

Index of pulses. For example, `1:10`.

Data Types: `int16`

Output Arguments

idx — Indices into SOC lookup table

`1-by-NumPulses` array

Indices into SOC lookup table.

Data Types: `int16`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plot

Plot pulse sequence data

Syntax

```
plot_handle = plot(psObj)
```

Description

`plot_handle = plot(psObj)` plots the data from a `Battery.PulseSequence` object.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plotIdentifiedPulses

Plot identified pulses

Syntax

```
plot_handle = plotIdentifiedPulses(psObj)
```

Description

`plot_handle = plotIdentifiedPulses(psObj)` plots identified pulses from a `Battery.PulseSequence` object.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plotLatestParameters

Plot latest pulse sequence parameters

Syntax

```
plot_handle = plotLatestParameters(psObj)
```

Description

`plot_handle = plotLatestParameters(psObj)` plots the latest pulse sequence parameters from a `Battery.PulseSequence` object.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plotSimulationResults

Plot pulse sequence simulation results

Syntax

```
plot_handle=plotSimulationResults(psObj)  
plot_handle=plotSimulationResults(psObj,param)
```

Description

`plot_handle=plotSimulationResults(psObj)` plots the simulation results of the pulse sequence based on the current parameter values.

`plot_handle=plotSimulationResults(psObj,param)` plots the simulation results of the pulse sequence based on the parameter values specified by the `Battery.Parameter` object.

Input Arguments

psObj — Instance of Battery.PulseSequence class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

param — Instance of Battery.Parameter class

`Battery.Parameter` object

`Battery.Parameter` object for the parameters that you want to analyze.

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

populatePulseParameters

Populate pulse parameters

Syntax

```
populatePulseParameters(psObj)
```

Description

`populatePulseParameters(psObj)` populates parameters in the `Battery.PulseSequence` object based on the series of pulse objects. If the pulse objects are new, updated, or filtered, `populatePulseParameters` updates the identified pulse indices, SOC breakpoints, and parameters objects in `Battery.PulseSequence`.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

removePulses

Remove pulses from sequence

Syntax

```
removePulses(psObj, idxRemove)
```

Description

`removePulses(psObj, idxRemove)` removes pulses from sequence specified by the `Battery.PulseSequence` object.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

idxRemove — Index of pulse objects to remove

`1:NumPulses` (default)

Index of pulse objects to remove. For example, `1:10`.

Data Types: `int16`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

repairTimeVector

Repair time vector

Syntax

```
repairTimeVector(psObj)  
repairTimeVector(psObj,MinDeltaT)
```

Description

`repairTimeVector(psObj)` repairs common problems with the experimental time vector on the `Battery.PulseSequence` object.

`repairTimeVector(psObj,MinDeltaT)` repairs common problems with the experimental time vector on the `Battery.PulseSequence` object using a minimum time difference.

Input Arguments

psObj — Instance of `Battery.PulseSequence` class

`Battery.PulseSequence` object

`Battery.PulseSequence` object for the pulse sequence that you want to analyze.

MinDeltaT — Minimum time difference

scalar

Index of pulse objects to remove. For example, `1:10`.

Data Types: `double`

Version History

Introduced in R2016b

See Also

`Battery.PulseSequence`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

Battery.Pulse

Define a single pulse event

Description

Use the `Battery.Pulse` object to define a single experimental pulse event. To create a pulse object, use the `Battery.PulseSequence` object function `createPulses`.

To use the `Battery.Pulse` object and methods, you need these products:

- Powertrain Blockset
- Curve Fitting Toolbox
- Optimization Toolbox
- Parallel Computing Toolbox
- Simulink Design Optimization

Creation

Syntax

```
pulseObj = Battery.Pulse(Battery.PulseSequence)
```

Description

MATLAB creates a `pulseObj = Battery.Pulse(Battery.PulseSequence)` object that defines a single pulse event.

Properties

Data — Raw data

1-by-5 array

An 1-by-5 array of pulse event data.

Array Element	Description	Unit
<code>Data(1,1)</code>	Time	s
<code>Data(1,2)</code>	Voltage	V
<code>Data(1,3)</code>	Current	A
<code>Data(1,4)</code>	Charge	A·s
<code>Data(1,5)</code>	State of charge (SOC)	Dimensionless

Data Types: double

InitialCapVoltage — Initial capacitor voltage

array

Initial voltage of each capacitor during a pulse event, in V. Property set by the `Battery.PulseSequence` object function `estimateParameters`, based on the simulated end voltage or a prior pulse.

Data Types: double

InitialChargeDeficit — Initial charge deficit

0.0 (default) | scalar

Initial charge deficit at start of pulse event, in A·s. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Example: 0.0

Data Types: double

idxLoad — Indices to load data

[1 0] (default)

Indices to load data where the pulse event load begins and ends. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Data Types: int16

idxRelax — Indices to relaxation data

[1 0] (default)

Indices to relaxation data where the pulse event relaxation begins and ends. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Data Types: int16

idxPulseSequence — Index to first pulse event data

[] (default)

Index to first pulse event data point in the `Battery.PulseSequence` object data. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Data Types: int16

IsDischarge — Discharge pulse

true (default)

Use this value to specify if pulse is a discharge pulse event. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Data Types: logical

Parameters — Battery.Parameters object properties

0-by-1 array

`Battery.Parameters` object containing the most recently determined battery equivalent circuit parameters. Property set by the `Battery.PulseSequence` object function `createPulses` when the function creates the series of `Battery.Pulse` objects.

Data Types: `function_handle`

ParametersHistory — Battery.ParametersHistory object properties

0-by-1 array

`Battery.ParametersHistory` object array containing the history of the battery equivalent circuit parameters through different estimation steps. The last element is the most recent parameter set.

Data Types: `function_handle`

Object Functions

<code>plot</code>	Plot pulse event data
<code>getLoadData</code>	Retrieve experimental data during load phase of pulse
<code>getRelaxationData</code>	Retrieve experimental data during relaxation phase of pulse
<code>getTransitionData</code>	Retrieve experimental data during transition phase of pulse

Examples

Create Battery.Pulse Object

This example shows how to create a `Battery.Pulse` object.

```
pulseObj = Battery.Pulse(psObj);
```

Version History

Introduced in R2016b

See Also

`Battery.Metadata` | `Battery.Parameters` | `Battery.PulseSequence` | `sdo.OptimizeOptions`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plot

Plot pulse event data

Syntax

```
plot_handle=plot(pulseObj)
```

Description

`plot_handle=plot(pulseObj)` plots the data from a `Battery.Pulse` object.

Input Arguments

pulseObj — Instance of `Battery.Pulse` class

`Battery.Pulse` object

`Battery.Pulse` object for the pulse event that you want to analyze.

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.Pulse`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

getLoadData

Retrieve experimental data during load phase of pulse

Syntax

```
LoadData = getLoadData(pulseObj,Buffer)
```

Description

LoadData = getLoadData(pulseObj,Buffer) retrieves the experimental data from a Battery.Pulse object during the load phase of a pulse.

Input Arguments

pulseObj — Instance of Battery.Pulse class

Battery.Pulse object

Battery.Pulse object for the pulse event that you want to analyze.

Buffer — Number of samples

vector

Number of buffer samples before and after the load data, in the form [BeforeBufferSize,AfterBufferSize]. Use the buffer to ensure that the estimation has sufficient data before and after a transition.

Output Arguments

LoadData — Load data

array

Load data during pulse event.

Data Types: double

Version History

Introduced in R2016b

See Also

Battery.Pulse

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

getRelaxationData

Retrieve experimental data during relaxation phase of pulse

Syntax

```
RelaxationData = getRelaxationData(pulseObj,Buffer)
```

Description

`RelaxationData = getRelaxationData(pulseObj,Buffer)` retrieves the experimental data from a `Battery.Pulse` object during the relaxation phase of a pulse.

Input Arguments

pulseObj — Instance of Battery.Pulse class

`Battery.Pulse` object

`Battery.Pulse` object for the pulse event that you want to analyze.

Buffer — Number of samples

vector

Number of buffer samples before and after the load data, in the form `[BeforeBufferSize,AfterBufferSize]`. Use the buffer to ensure that the estimation has sufficient data before and after a transition.

Output Arguments

RelaxationData — Relaxation data

array

Relaxation data during pulse event.

Data Types: `double`

Version History

Introduced in R2016b

See Also

`Battery.Pulse`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

getTransitionData

Retrieve experimental data during transition phase of pulse

Syntax

```
[TransitionDataBefore,TransitionDataAfter]=getTransitionData(pulseObj,idx)  
[TransitionDataBefore,TransitionDataAfter]=getTransitionData(pulseObj,idx,  
Buffer)
```

Description

[TransitionDataBefore,TransitionDataAfter]=getTransitionData(pulseObj,idx) retrieves the transition data from a Battery.Pulse object during the transition phase of a pulse.

[TransitionDataBefore,TransitionDataAfter]=getTransitionData(pulseObj,idx, Buffer) retrieves buffered experimental data from a Battery.Pulse object during the transition phase of a pulse.

Input Arguments

pulseObj — Instance of Battery.Pulse class

Battery.Pulse object

Battery.Pulse object for the pulse event that you want to analyze.

idx — Transition data index

scalar

Index of transition data.

Data Types: int16

Buffer — Number of samples

vector

Number of buffer samples before and after the load data, in the form [BeforeBufferSize,AfterBufferSize]. Use the buffer to ensure that the estimation has sufficient data before and after a transition.

Output Arguments

TransitionDataBefore — Data before transition

array

Data before transition during pulse event.

Data Types: double

TransitionDataAfter — Data after transition

array

Data after transition during pulse event.

Data Types: double

Version History

Introduced in R2016b

See Also

Battery.Pulse

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

Battery.Parameters

Define battery equivalent circuit parameters

Description

Use the `Battery.Parameters` object to define the battery equivalent circuit parameters. `Battery.Parameters` objects are contained in the `Battery.PulseSequence` and `Battery.Pulse` objects. The pulse sequence estimation sets some of the `Battery.Parameters` properties. You can override the properties by manually setting the properties. The number of pulses, N , in the dataset determines the length of each array.

Creation

Syntax

```
paramObj = Battery.Parameters
```

Description

MATLAB creates a `paramObj = Battery.Parameters` object that defines the battery equivalent circuit parameters.

Properties

SOC — State of charge breakpoints

1-by-11 array (default)

A 1-by- N array of the state of charge (SOC) breakpoints.

Data Types: `double`

Em — Open circuit voltage

1-by-11 array (default)

A 1-by- N array of the open circuit voltage, in V.

Data Types: `double`

EmMin — Minimum open circuit voltage

1-by-11 array (default)

A 1-by- N array of the minimum open circuit voltage, in V.

Data Types: `double`

EmMax — Maximum open circuit voltage

1-by-11 array (default)

A 1-by- N array of the maximum open circuit voltage, in V.

Data Types: double

R0 — Terminal resistance

1-by-11 array (default)

A 1-by-N array of the terminal resistance, in Ohms.

Data Types: double

R0Min — Minimum terminal resistance

1-by-11 array (default)

A 1-by-N array of the minimum terminal resistance, in Ohms.

Data Types: double

R0Max — Maximum terminal resistance

1-by-11 array (default)

A 1-by-N array of the maximum terminal resistance, in Ohms.

Data Types: double

Rx — RC pair resistance

3-by-11 array (default)

A 3-by-N array of the RC pair resistance, in Ohms.

Data Types: double

RxMin — Minimum RC pair resistance

3-by-11 array (default)

A 3-by-N array of the minimum RC pair resistance, in Ohms.

Data Types: double

RxMax — Maximum RC pair resistance

3-by-11 array (default)

A 3-by-N array of the maximum RC pair resistance, in Ohms.

Data Types: double

Tx — RC pair time constant

3-by-11 array (default)

A 3-by-N array of the RC pair time constant, in s.

Data Types: double

TxMin — Minimum RC pair time constant

3-by-11 array (default)

A 3-by-N array of the minimum RC pair time constant, in s.

Data Types: double

TxMax — Maximum RC pair time constant

3-by-11 array (default)

A 3-by-N array of the maximum RC pair time constant, in s.

Data Types: double

Object Functions

lookupSocFromVoltage Determine SOC from voltage
plot Plot battery parameter data

Examples

Create Battery.Parameters Object

This example shows how to create a `Battery.Parameters` object.

Create a `Battery.Parameters` object.

```
paramObj=Battery.Parameters;
```

Version History

Introduced in R2016b

See Also

`Battery.Metadata` | `Battery.PulseSequence` | `Battery.Pulse` | `sdo.OptimizeOptions`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

lookupSocFromVoltage

Determine SOC from voltage

Syntax

```
SOC=lookupSocFromVoltage(paramObj,Voltage)
```

Description

`SOC=lookupSocFromVoltage(paramObj,Voltage)` calculates the state of charge (SOC) from the voltage for a given open-circuit voltage. Use `lookupSocFromVoltage` after you know the open-circuit voltage, *Em*, value.

Input Arguments

paramObj — Instance of `Battery.Parameters` class

`Battery.Parameters` object

`Battery.Parameters` object for the battery that you want to analyze.

Voltage — Open circuit voltage

scalar

Open circuit voltage, in V.

Data Types: char

Output Arguments

SOC — State of charge

scalar

State of charge.

Data Types: double

Version History

Introduced in R2016b

See Also

`Battery.Parameters`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

plot

Plot battery parameter data

Syntax

```
plot_handle=plot(paramObj)  
plot_handle=plot(paramObj,LegendNames)
```

Description

`plot_handle=plot(paramObj)` plots the data from a `Battery.Parameters` object.

`plot_handle=plot(paramObj,LegendNames)` plots the data from a `Battery.Parameters` object with the legend names.

Input Arguments

paramObj — Instance of `Battery.Pulse` class

`Battery.Parameters` object

`Battery.Parameters` object for the battery that you want to analyze.

LegendNames — Plot legends

character vector

Name of plot legends.

Data Types: char

Output Arguments

plot_handle — Plot handle

object handle

Handles to plot objects.

Data Types: `function_handle`

Version History

Introduced in R2016b

See Also

`Battery.Parameters`

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

Battery.Metadata

Define battery metadata

Description

Use the `Battery.Metadata` object to define the battery metadata. A `Battery.PulseSequence` object contains the `Battery.Metadata` object. You must specify the metadata values.

Creation

Syntax

```
batmetaObj = Battery.Metadata
```

Description

MATLAB creates a `batmetaObj = Battery.Metadata` object that defines the battery metadata.

Properties

BatteryId — Battery identification

character vector

Battery identification name.

Data Types: `double`

RatingAh — Battery rating

character vector

Battery rating.

Data Types: `char`

Name — Dataset name

character vector

Dataset name.

Data Types: `char`

Date — Dataset date

character vector

Dataset date.

Data Types: `char`

Source — Dataset source

character vector

Dataset source.

Data Types: char

TestType – Experimental data type

character vector

Test type, for example charge or discharge.

Data Types: char

TestCurrent – Test current

scalar

Test current, in A.

Data Types: double

TestTemperature – Test temperature

scalar

Test temperature, in C.

Data Types: double

Examples

Create Battery.Metadata Object and Set Properties

This example shows how to create a Battery.Metadata object and set properties.

Create a Battery.Metadata object.

```
batmetaObj=Battery.Metadata;
```

Set Battery.Metadata properties.

```
batmetaObj.BatteryId='myBatteryId';
batmetaObj.RatingAh='myRatingAh';
batmetaObj.Name='myName';
batmetaObj.Date='myDate';
batmetaObj.Source='mySource';
batmetaObj.TestType='Charge';
batmetaObj.TestCurrent=300;
batmetaObj.TestCurrent=120;
```

Display Battery.Metadata properties.

```
disp(batmetaObj)
```

Version History

Introduced in R2016b

See Also

Battery.Parameters | Battery.PulseSequence | Battery.Pulse

Topics

“Generate Parameter Data for Datasheet Battery Block”

“Generate Parameter Data for Equivalent Circuit Battery Block”

Apps

Virtual Vehicle Composer

Configure, build, and analyze a virtual automotive vehicle

Description

The **Virtual Vehicle Composer** app enables you to configure and build a virtual vehicle that you can use for system-level performance analysis, including component sizing, fuel economy, drive cycle tracking, software integration testing, and hardware-in-the-loop (HIL) testing. Use the app to quickly enter your vehicle parameter data, build a virtual vehicle model, run test scenarios, and analyze the results.

The virtual vehicle model contains the blocks and reference application subsystems available with Powertrain Blockset, Vehicle Dynamics Blockset™, Simscape™ Driveline™, and Simscape Electrical™. You can use the app to quickly configure the architecture and enter parameter data.

If you have Powertrain Blockset, use the app to:



- Analyze design tradeoffs and size components.
- Configure hybrid-electric vehicle (HEV) architectures.






If you have Vehicle Dynamics Blockset, use the app to:

- Analyze ride-and-handling effects of standard test maneuvers.
- Visualize your virtual vehicle in the Unreal Engine® simulation environment.

If you have Simscape Driveline and Simscape Electrical, use the app to configure the vehicle plant and powertrain architecture with Simscape subsystems.

To build, operate, and analyze your virtual vehicle, use the **Composer** tab. The options and settings depend on the available products.

Step	Section	Button	Description
1	Configure		Setup Select New , then specify: <ul style="list-style-type: none"> • Project, folder, and model name <hr/> Note The combined folder and project name must be less than 80 characters. <ul style="list-style-type: none"> • Powertrain architecture • Model template • Vehicle dynamics
2			Data and Calibration Specify the chassis, tire, brake type, powertrain, environment, and driver. For each selection, enter the vehicle parameter data.

Step	Section	Button	Description
3			Scenario and Test Select the virtual vehicle driving maneuvers and add them to the test plan. Options include drive cycle scenarios for longitudinal studies and standard test maneuvers for vehicle dynamics studies.
4			Logging Select the model signal data to log when operating your virtual vehicle. Options include vehicle position, velocity, and acceleration.
5	Build		Virtual Vehicle Build your virtual vehicle. When you build, the Virtual Vehicle Composer creates a Simulink model that contains the vehicle architecture and the data that you specify in the configuration.
6	Operate		Run Test Plan Use the Simulation Manager to operate your model using the test plans that you specify in step 3.
7	Analyze		Simulation Data Inspector Use the Simulation Data Inspector to view and inspect the simulation signals that you select in step 4.

Required Products

The **Virtual Vehicle Composer** requires either of these products:

- “Powertrain Blockset”
- “Vehicle Dynamics Blockset”



If you want to run your virtual vehicle in the Unreal Engine 3D simulation environment, see the requirements in “Unreal Engine Simulation Environment Requirements and Limitations” (Vehicle Dynamics Blockset).

If you have these Simscape products, you can use the app to configure the vehicle plant with Simscape subsystems:

- “Simscape Driveline”
- “Simscape Electrical”

Setup

Use the app to quickly enter your virtual vehicle class, powertrain architecture, model template, and vehicle dynamics.

Parameter	Description
Powertrain architecture	<p>Specify the powertrain architecture. By default, the parameter is set to <code>Conventional Vehicle</code>. The conventional vehicle architecture has a spark-ignition (SI) or compression-ignition (CI) internal combustion engine, transmission, chassis, and associated powertrain control algorithms. You can also select <code>Electric Vehicle 1EM</code> to specify an electric vehicle (EV) powertrain architecture.</p> <p>If you have Powertrain Blockset, you can specify model architectures for hybrid electric vehicles (HEVs).</p> <p>The HEV and EV model architectures include an internal combustion engine, chassis, transmission, battery, motor, generator, and associated powertrain control algorithms.</p>
Model template	<p>Specify a Simulink or Simscape vehicle plant and powertrain architecture. By default, the virtual vehicle uses a Simulink model template. If you have Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simscape subsystems that model a conventional vehicle.</p> <p>If you have Simscape Driveline and Simscape Electrical, you can configure the vehicle plant and powertrain architecture with Simscape subsystems that model EVs and HEVs.</p>
Vehicle Dynamics	<p>Configure the virtual vehicle dynamics.</p> <ul style="list-style-type: none">  <p>Longitudinal vehicle dynamics — Suitable for fuel economy and energy management analysis.</p>  <p>Combined longitudinal and lateral vehicle dynamics — If you have Vehicle Dynamics Blockset, you can specify dynamics suitable for vehicle handling, stability, and ride comfort analysis.</p> <p>The virtual vehicle uses the Z-up coordinate system as defined in SAE J670 and ISO 8855. For more information, see “Coordinate Systems in Vehicle Dynamics Blockset” (Vehicle Dynamics Blockset).</p>

Data and Calibration

Use the app to quickly enter your virtual vehicle parameter data for the vehicle architecture, vehicle dynamics model, chassis, powertrain, and driver. For each selection, enter the parameter data.

Parameter	Description
Chassis	Select the chassis type.

Parameter	Description
Tire	Select the tire model and tire data. The available parameters depend on the available products, vehicle architecture, and vehicle model.
Brake Type	Select the brake type, including <code>Disc</code> , <code>Drum</code> , and <code>Mapped</code> . Use the Brake Control Unit parameter to specify the brake control.
Powertrain	Select the engine, transmission, drivetrain, differential system, and electrical system parameters for your virtual vehicle. The available parameters depend on the products, vehicle architecture, and vehicle model.
Driver	Select the driver. The parameter setting <code>Longitudinal Driver</code> implements a longitudinal speed-tracking controller. If you have Vehicle Dynamics Blockset, you can set Driver to <code>Predictive Driver</code> to track longitudinal velocity and a lateral reference displacement.
Environment	The parameter setting <code>Standard Ambient</code> implements an ambient environment model.
Steering System	If you have Vehicle Dynamics Blockset and set Vehicle dynamics to <code>Combined longitudinal and lateral vehicle dynamics</code> , you can specify the steering system, including <code>Kinematic Steering</code> , <code>Dynamic Steering</code> , and <code>Mapped Steering</code> .
Suspension	If you have Vehicle Dynamics Blockset and set Vehicle dynamics to <code>Combined longitudinal and lateral vehicle dynamics</code> , you can specify the suspension system, including <code>Kinematics and Compliance Independent Suspension</code> and <code>MacPherson Front Suspension Solid Axle Rear Suspension</code> .

Scenario and Test

Select the scenario to use to test your virtual vehicle.

If you set **Scenario** to `Drive Cycle`, you can use:

- Drive cycles from predefined sources. By default, the block includes the FTP–75 drive cycle. To install additional drive cycles from a support package, see “Install Drive Cycle Data”. The support package has drive cycles that include the gear shift schedules, for example, JC08 and CUEDC.
- Workspace variables that define your own drive cycles.
- `.mat`, `.xls`, `.xlsx`, or `.txt` files.
- Wide open throttle (WOT) parameters, including initial and nominal reference speed, deceleration start time, and final reference speed.

If you have Vehicle Dynamics Blockset and set **Vehicle dynamics** to `Combined longitudinal and lateral vehicle dynamics`, you can select maneuvers for vehicle handling, stability, and ride analysis. Maneuvers include:

- Double Lane Change
- Increasing Steer
- Constant Radius

If you want to run your virtual vehicle in the Unreal Engine 3D simulation environment, set **3D Simulation** to `Enable`. For hardware requirements, see “Unreal Engine Simulation Environment Requirements and Limitations” (Vehicle Dynamics Blockset).

Logging

Select the model signal data to log when operating your virtual vehicle. Options include vehicle position, velocity, and acceleration. By default, the app lists frequently used signals.

Virtual Vehicle

Build your virtual vehicle. When you build, the **Virtual Vehicle Composer** creates a Simulink model that contains the specified vehicle architecture and data.

Test Plan

Simulate your model in the scenario that you specified in **Vehicle Scenario and Test**.

Simulation Data Inspector

Use the Simulation Data Inspector to view and inspect the simulation signals.

If you run your virtual vehicle through more than one test scenario, the Simulation Data Inspector displays the results from the last simulation. To see results from previous simulations, load the archived results.

The screenshot shows the Virtual Vehicle Composer interface. The main workspace displays a car icon and a dropdown menu for 'Chassis' set to 'Vehicle Body 3DOF Longitudinal'. Below this is a 'Parameters' table with the following data:

	Paramete...	Description	Unit	Value
1	PIntVehMass	Vehicle mass	kg	1623
2	PIntVehDst...	Longitudinal distance from ...	m	1.09
3	PIntVehDst...	Longitudinal distance from ...	m	1.7
4	PIntVehCG...	Vertical distance from cent...	m	0.3
5	PIntVehInitV...	Vehicle initial vertical position	m	0

Open the Virtual Vehicle Composer App

- MATLAB Toolstrip: On the **Apps** tab, under **Automotive**, click the app icon.
- MATLAB Command Window: Enter `virtualVehicleComposer`.

Examples

- “Get Started with the Virtual Vehicle Composer”

Parameters

Setup

Project name — Project name

VVProj (default)

Name of virtual vehicle project, specified as a character vector.

Note The combined folder and project name must be less than 80 characters.

Data Types: char

Project folder — Project folder

C:\Users\UserName\MATLAB\Projects\examples (default)

Project folder path, specified as a character vector.

Note The combined folder and project name must be less than 80 characters.

Data Types: char

Model name — Virtual vehicle model name

ConfiguredVirtualVehicleModel (default)

Name of virtual vehicle model, specified as a character vector.

Data Types: char

Powertrain architecture — Hybrid electric, conventional, or electric vehicle

Conventional Vehicle|Electric Vehicle 1EM|Hybrid Electric IPS|Hybrid Electric MM|Hybrid Electric P0|Hybrid Electric P1|Hybrid Electric P2|Hybrid Electric P3|Hybrid Electric P4

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Conventional Vehicle	✓	✓	<p>Model architecture for a vehicle with a SI or CI internal combustion engine, transmission, and associated powertrain control algorithms.</p> <p>If you have Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Electric Vehicle 1EM	✓	✓	<p>Model architecture for an electric vehicle (EV) with a motor-generator, battery, direct-drive transmission, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric IPS	✓		<p>Model architecture for a input power split (IPS) hybrid electric vehicle (HEV) with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric MM	✓		<p>Model architecture for a multimode HEV with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric P0	✓		<p>Model architecture for a HEV P0 with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Hybrid Electric P1	✓		<p>Model architecture for a HEV P1 with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric P2	✓		<p>Model architecture for a HEV P2 with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric P3	✓		<p>Model architecture for a HEV P3 with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>
Hybrid Electric P4	✓		<p>Model architecture for a HEV P4 with an internal combustion engine, transmission, battery, motor, generator, and associated powertrain control algorithms.</p> <p>If you have Simscape Electrical and Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simulink or Simscape model templates.</p>

Model template – Vehicle plant and powertrain architecture template

Simulink (default) | Simscape

Use the parameter to specify a Simulink or Simscape vehicle plant and powertrain architecture. By default, the virtual vehicle uses a Simulink model template. If you have Simscape Driveline, you can configure the vehicle plant and powertrain architecture with Simscape subsystems that model a conventional vehicle.

If you have Simscape Driveline and Simscape Electrical, you can configure the vehicle plant and powertrain architecture with Simscape subsystems that model EVs and HEVs.

Vehicle dynamics — Virtual vehicle longitudinal or lateral vehicle dynamics

Longitudinal vehicle dynamics (default) | Combined longitudinal and lateral vehicle dynamics

Use the parameter to configure the virtual vehicle dynamics.



Longitudinal vehicle dynamics — Suitable for fuel economy and energy management analysis.



Combined longitudinal and lateral vehicle dynamics — If you have Vehicle Dynamics Blockset, you can specify dynamics suitable for vehicle handling, stability, and ride comfort analysis.

The virtual vehicle uses the Z-up coordinate system as defined in SAE J670 and ISO 8855. For more information, see “Coordinate Systems in Vehicle Dynamics Blockset” (Vehicle Dynamics Blockset).

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Longitudinal vehicle dynamics	✓	✓	Model suitable for fuel economy and energy management analysis.
Combined longitudinal and lateral vehicle dynamics		✓	Model suitable for vehicle handling, stability, and ride comfort analysis.

Data and Calibration

Chassis — Chassis type

Vehicle Body 1DOF Longitudinal | Vehicle Body 3DOF Longitudinal | Vehicle Body 6DOF Longitudinal and Lateral

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Vehicle Body 1DOF Longitudinal	✓	✓	Chassis model for 1DOF longitudinal vehicle dynamics. Available when you set Vehicle dynamics to Longitudinal vehicle dynamics.
Vehicle Body 3DOF Longitudinal	✓	✓	Chassis model for 3DOF longitudinal vehicle dynamics. Available when you set Vehicle dynamics to Longitudinal vehicle dynamics.
Vehicle Body 6DOF Longitudinal and Lateral		✓	Chassis model for 3DOF longitudinal vehicle dynamics. Available when you set Vehicle dynamics to Combined longitudinal and lateral vehicle dynamics.

Tire – Virtual vehicle tires

MF Tires Longitudinal | Fiala Tires Longitudinal and Lateral | MF Tires Longitudinal and Lateral | Longitudinal Combined Slip Tire

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
MF Tires Longitudinal	✓	✓	Tire model suitable for longitudinal vehicle dynamics studies, including fuel economy and energy management analysis.
Fiala Tires Longitudinal and Lateral		✓	Tire models suitable for lateral vehicle dynamics studies, including vehicle handling, stability, and ride comfort analysis. Implements a simplified tire with lateral and longitudinal slip capability. Uses a translational friction model to calculate the forces and moments during combined longitudinal and lateral slip. If you do not have the tire coefficients needed by the Magic Formula, consider using this setting for studies that do not involve extensive nonlinear combined lateral slip or lateral dynamics.
MF Tires Longitudinal and Lateral		✓	Tire models suitable for lateral vehicle dynamics studies, including vehicle handling, stability, and ride comfort analysis. Tire model implements the longitudinal and lateral behavior of a wheel characterized by the Magic Formula. You can use Tire Data

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Longitudinal Combined Slip Tire		✓	parameter to specify fitted tire data sets provided by the Global Center for Automotive Performance Simulation (GCAPS) for tires, including: <ul style="list-style-type: none"> • Light passenger car 205/60R15 • Mid-size passenger car 235/45R18 • Performance car 225/40R19 • SUV 265/50R20 • Light truck 275/65R18 • Commercial truck 295/75R22.5

Brake Type – Virtual vehicle brakes

Disc | Drum | Mapped

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Disc	✓	✓	Brake model converts the brake cylinder pressure into a braking force.
Drum	✓	✓	Brake model converts the applied force and brake geometry into a net braking torque.
Mapped	✓	✓	Brake model is a function of the wheel speed and applied brake pressure.

Brake Control Unit – Brake control

Bang Bang ABS | Open Loop | Five-State ABS and TCS

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Bang Bang ABS	✓	✓	Anti-lock braking system (ABS) feedback controller that switches between two states to regulate wheel slip. The bang-bang control minimizes the error between the actual slip and the desired slip. For the desired slip, the controller uses the slip value at which the mu-slip curve reaches a peak value. This desired slip value is optimal for minimum braking distance.
Open Loop	✓	✓	Open loop brake control. The controller sets the brake pressure command to a reference brake pressure based on the brake command.
Five-State ABS and TCS	✓	✓	Five-state ABS and traction control system (TCS) that uses logic-switching based on wheel deceleration and vehicle acceleration to control the braking pressure at each wheel. Consider using five-state ABS and TCS control to prevent wheel lock-up, decrease braking distance, or maintain yaw stability during the maneuver. The default ABS parameters are set to work on roads that have a constant friction coefficient scaling factor of 0.6.

Engine – Virtual vehicle engine

Simple Engine (SI) | Simple Engine (CI) | CI Engine | CI Mapped Engine | SI Engine | SI Mapped Engine | SI DL Engine

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Simple Engine (SI)	✓	✓	Simplified SI engine model using a maximum torque verses engine speed table, two scalar fuel mass properties, and one scalar engine efficiency parameter to estimate engine torque and fuel flow. Selecting Simple Engine SI sets the Engine Control Unit parameter to Simple ECU.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Simple Engine (CI)	✓	✓	<p>Simplified CI engine model using a maximum torque verses engine speed table, two scalar fuel mass properties, and one scalar engine efficiency parameter to estimate engine torque and fuel flow.</p> <p>Selecting Simple Engine CI sets the Engine Control Unit parameter to Simple ECU.</p>
CI Engine	✓		<p>Compression-ignition (CI) engine from intake to the exhaust port.</p> <p>Selecting CI Engine sets the Engine Control Unit parameter to CI Engine Controller.</p>
CI Mapped Engine	✓	✓	<p>Mapped CI engine model using power, air mass flow, fuel flow, exhaust temperature, efficiency, and emission performance lookup tables.</p> <p>Selecting CI Mapped Engine sets the Engine Control Unit parameter to CI Engine Controller.</p>
SI Engine	✓		<p>Spark-ignition (SI) engine from intake to exhaust port.</p> <p>Selecting SI Engine sets the Engine Control Unit parameter to SI Engine Controller.</p>
SI Mapped Engine	✓	✓	<p>Mapped SI engine model using power, air mass flow, fuel flow, exhaust temperature, efficiency, and emission performance lookup tables.</p> <p>Selecting SI Mapped Engine sets the Engine Control Unit parameter to SI Engine Controller.</p>

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
SI DL Engine	✓		<p>Deep learning SI engine.</p> <p>Available if you have the Deep Learning Toolbox™ and Statistics and Machine Learning Toolbox™ licenses. Use this setting to generate a dynamic deep learning SI engine model to use for powertrain control, diagnostic, and estimator algorithm design.</p> <p>Selecting SI DL Engine sets the Engine Control Unit parameter to SI Engine Controller.</p>

Transmission – Virtual vehicle transmission

Ideal Fixed Gear Transmission | Automatic Transmission with Torque Converter | Automated Manual Transmission | No Transmission

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Ideal Fixed Gear Transmission	✓	✓	Idealized fixed-gear transmission without a clutch or synchronization. Use this setting to model the overall gear ratio and power loss when you do not need a detailed transmission model.
Automatic Transmission with Torque Converter	✓		Automatic transmission with a torque converter.
Automated Manual Transmission	✓		Ideal automated transmission (AMT). An AMT is a manual transmission with additional actuators and an electronic control unit (ECU) to regulate clutch and gear selection based on commands from a controller. Specify the number of gears as an integer vector with corresponding gear ratios, inertias, viscous damping, and efficiency factors. The clutch and synchronization engagement rates are linear and adjustable.
No Transmission	✓		No transmission.

Dependencies

To enable this parameter, set **Powertrain architecture** to any of these options:

- Conventional Vehicle
- Hybrid Electric Vehicle P0
- Hybrid Electric Vehicle P1
- Hybrid Electric Vehicle P2
- Hybrid Electric Vehicle P3
- Hybrid Electric Vehicle P4

Transmission Control Unit – Virtual vehicle transmission control

PRNDL Controller

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
PRNDL Controller	✓	✓	Controller that optimizes forward, reverse, neutral, park, and N-speed gear shift scheduling for fuel economy.

Dependencies

To enable this parameter, set **Powertrain architecture** to any of these options:

- Conventional Vehicle
- Hybrid Electric Vehicle P0
- Hybrid Electric Vehicle P1
- Hybrid Electric Vehicle P2
- Hybrid Electric Vehicle P3
- Hybrid Electric Vehicle P4

Drivetrain – Virtual vehicle drivetrain

Front Wheel Drive | Front Wheel Drive | All Wheel Drive

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Front Wheel Drive	✓	✓	Configure vehicle with front wheel drive.
Rear Wheel Drive	✓	✓	Configure vehicle with rear wheel drive.
All Wheel Drive	✓	✓	Configure vehicle with all wheel drive.

Differential System – Virtual vehicle differential system

Open Differential | Active Differential | Limited Slip Differential

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Open Differential	✓	✓	Differential as a planetary bevel gear train. The block matches the driveshaft bevel gear to the crown (ring) bevel gear. You can specify: <ul style="list-style-type: none"> Carrier-to-driveshaft ratio Crown wheel location Viscous and damping coefficients for the axles and carrier
Active Differential	✓	✓	Active differential that accounts for the power transfer from the transmission to the axles. The model implements the active differential as an open differential coupled to either a spur or a planetary differential gear set.
Limited Slip Differential	✓	✓	Differential as a planetary bevel gear train. The block matches the driveshaft bevel gear to the crown (ring) bevel gear. You can specify: <ul style="list-style-type: none"> Carrier-to-driveshaft ratio Crown wheel location Viscous and damping coefficients for the axles and carrier Type of slip coupling

Electrical System – Virtual vehicle electric machine and energy storage

Electrical System 1EM Battery | Electrical System 2EM | Electrical System 1EM

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Electrical System Settings	Powertrain Blockset	Vehicle Dynamics Blockset	Powertrain Architecture	Description
Electrical System 1EM Battery	✓		Electrical System 1EM	<ul style="list-style-type: none"> Mapped motor and drive electronics operating in torque-control mode. Lithium ion battery model based on discharge characteristics taken at different temperatures.

Electrical System Settings	Powertrain Blockset	Vehicle Dynamics Blockset	Powertrain Architecture	Description
Electrical System 1EM Battery with Energy Storage set to Ideal Voltage Source	✓	✓	Electrical System 1EM	<ul style="list-style-type: none"> • Mapped motor and drive electronics operating in torque-control mode. • Ideal voltage source battery model.
Electrical System 2EM	✓		<ul style="list-style-type: none"> • Hybrid Electric Vehicle IPS • Hybrid Electric Vehicle MM 	<ul style="list-style-type: none"> • Two mapped motors and drive electronics operating in torque-control mode. • Lithium ion battery model based off of discharge characteristics taken at different temperatures.
Electrical System 1EM	✓		<ul style="list-style-type: none"> • Hybrid Electric Vehicle P0 • Hybrid Electric Vehicle P1 • Hybrid Electric Vehicle P2 • Hybrid Electric Vehicle P3 • Hybrid Electric Vehicle P4 	<ul style="list-style-type: none"> • Two mapped motors and drive electronics operating in torque-control mode. • Lithium ion battery model with DC-DC conversion.

Use the **Electrical Machine** parameters to specify a mapped motor and drive electronics operating in torque-control mode.

Use the **Energy Storage** parameters to specify a datasheet battery model for a lithium-ion battery.

Vehicle Control Unit – HEV and EV virtual vehicle control

EV 1EM | HEVIPs RuleBased | HEVMM RuleBased | HEVP0 Optimal | HEVP1 Optimal | HEVP2 Optimal | HEVP3 Optimal | HEVP4 Optimal

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Powertrain Architecture	Description
EV 1EM	✓	✓	Electric Vehicle	Controls the motor with torque arbitration and power management. Implements regenerative braking.
HEVIPS RuleBased	✓		Hybrid Electric Vehicle IPS	Controls the motor, generator, and engine through a set of rules and decision logic implemented in Stateflow.
HEVMM RuleBased	✓		Hybrid Electric Vehicle MM	
HEVP0 Optimal	✓		Hybrid Electric Vehicle P4	Implements an equivalent consumption minimization strategy (ECMS) to control the energy management of hybrid electric vehicles (HEVs). The strategy optimizes the torque split between the engine and motor to minimize energy consumption while maintaining the battery state of charge (SOC).
HEVP1 Optimal	✓		Hybrid Electric Vehicle P4	
HEVP2 Optimal	✓		Hybrid Electric Vehicle P4	
HEVP3 Optimal	✓		Hybrid Electric Vehicle P4	
HEVP4 Optimal	✓		Hybrid Electric Vehicle P4	

Driver – Virtual vehicle driver

Longitudinal Driver | Predictive Driver

If you have Vehicle Dynamics Blockset, you can set **Driver** to Predictive Driver to track longitudinal velocity and a lateral reference displacement.

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Longitudinal Driver	✓	✓	Implements a longitudinal speed-tracking controller.
Predictive Driver		✓	Track longitudinal velocity and a lateral reference displacement. Available when you set Vehicle dynamics to Combined longitudinal and lateral vehicle dynamics.

Environment – Virtual vehicle environment

Standard Ambient

The parameter setting Standard Ambient implements an ambient environment model.

Steering System – Steering

Mapped | Kinematic | Dynamic

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Mapped		✓	Mapped rack-and-pinion steering model.
Kinematic		✓	Kinematic model for ideal rack-and-pinion steering. Gears convert the steering rotation into linear motion.
Dynamic		✓	Dynamic model for ideal rack-and-pinion steering. Gears convert the steering rotation into linear motion.

Suspension – Suspension

Kinematics and Compliance Independent Suspension | MacPherson Front Suspension
Solid Axle Rear Suspension

These parameters depend on the available products. This table summarizes the parameters available with Powertrain Blockset or Vehicle Dynamics Blockset.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
Kinematics and Compliance Independent Suspension		✓	Kinematics and compliance (K & C) test suspension characteristics measured from simulated or actual laboratory suspension tests.

Setting	Powertrain Blockset	Vehicle Dynamics Blockset	Description
MacPherson Front Suspension Solid Axle Rear Suspension		✓	Independent MacPherson suspension for multiple axles with multiple tracks per axle.

Programmatic Use

Entering the command `virtualVehicleComposer` opens a new session of the app, enabling you to configure, build, and analyze your virtual vehicle.

Version History

Introduced in R2022a

Configure vehicles with Simscape subsystems

If you have these Simscape products, you can use the **Virtual Vehicle Composer** app to configure the vehicle plant with Simscape subsystems.

- Simscape Driveline
- Simscape Electrical

When you build your virtual vehicle, on the **Setup** tab, set **Model template** to Simscape.

The app provides the Simscape subsystem templates for longitudinal vehicle analysis.

See Also

Topics

“Get Started with the Virtual Vehicle Composer”

“Simulation Data Inspector”

“How 3D Simulation for Vehicle Dynamics Blockset Works” (Vehicle Dynamics Blockset)

