
Contents

Foreword	xi
Chapter 1. Role of Simulation in the Design Cycle of Complex Technological Systems	1
1.1. Approach to the design of complex systems	2
1.1.1. Engineering activities in the design cycle.	3
1.1.2. Modeling and simulation roles in the design cycle	4
1.1.3. Validation and verification	13
1.2. Book objectives and content.	14
1.2.1. Modeling principles	14
1.2.2. Approaches and analysis tools	16
1.2.3. Multi-physics or multidisciplinary knowledge.	17
1.2.4. Problem-based approach.	17
Chapter 2. Fundamental Concepts of Lumped Parameter-Based Multi-Physics Modeling	19
2.1. Definition and modeling levels of mechatronic systems	20
2.1.1. From mechanical systems to mechatronic systems	20
2.1.2. Modeling levels in the design of mechatronic systems	22
2.2. Modeling of mechatronic systems with lumped parameters	23
2.2.1. Lumped parameters.	23
2.2.2. Port and causality notions	24
2.2.3. Kirchhoff's laws and network approach	27
2.2.4. Representation of energy flows.	30
2.2.5. Types of generic elements.	30
2.3. Multi-physics modeling of a power window system.	34
2.3.1. Description of the system and of modeled domains.	34
2.3.2. Domains and elements used for modeling	35

2.3.3. Incremental modeling	37
2.3.4. Graphic or text modeling	39
2.3.5. Transient control and simulations	39
2.4. Revision exercises and multiple-choice questions	40
2.4.1. Revision of Kirchhoff's laws in multi-domain modeling	40
2.4.2. Questions related to the power window system example.	42
2.4.3. Multiple-choice questions related to the modeling of technological components	44
2.5. Problems	46
2.5.1. Analysis of the conditioning electronics of a pressure sensor	46
2.5.2. Modeling the power transmission of an electric scooter	49
2.5.3. Modeling a hydraulic actuation system for launcher thrust vector control	53
2.5.4. Electromagnetic interferences	58
Chapter 3. Setting Up a Lumped Parameter Model	65
3.1. Introduction to the notion of adapted model	66
3.1.1. Chapter objectives and approach.	66
3.1.2. Problem under study	67
3.1.3. Importance of the type of excitation	68
3.2. Identifying the main effects	69
3.2.1. Systematic setup of domains and effects	69
3.2.2. From geometry to network	70
3.3. Modeling approaches and selection of adapted models	73
3.3.1. Incremental modeling by increasing complexity	73
3.3.2. Model reduction by activity index analysis.	77
3.3.3. Model reduction by design of the experiment or by comparison of effects	80
3.4. Introductory exercises related to setting up models with lumped parameters	83
3.4.1. Building up analytical skills.	84
3.4.2. Geometry/network link: power steering analysis	88
3.4.3. Systematic analysis of effects: analysis of a direct injection system by common rail	91
3.5. Problems related to the choice of modeling level	93
3.5.1. Thermal response of a TGV motor – deductive approach	93
3.5.2. Modeling of a power steering torque sensor – geometry analysis	95
3.5.3. Calculation of the short-circuit torque of a submarine propulsion motor – model reduction	99

Chapter 4. Numerical Simulation of Multi-Physics Systems.	103
4.1. From mathematical model to numerical model.	104
4.1.1. Mathematical models – various systems of equations	104
4.1.2. Advantages of integration.	107
4.1.3. Various representations of a system of equations	110
4.2. From numerical model to computer simulated model	112
4.2.1. Causality	112
4.2.2. Reaching consistency	113
4.2.3. Bond graph modeling	117
4.3. Simulation: numerical resolution of ODEs	124
4.3.1. Review and definitions.	124
4.3.2. Separate steps methods	125
4.3.3. Linked steps methods	129
4.3.4. Stability domain of a method for solving ODE	131
4.4. The main sources of error in modeling and simulation	131
4.4.1. Model representativity	131
4.4.2. Validity of parameters	133
4.4.3. System initialization	133
4.4.4. Numerical robustness	134
4.4.5. Observation errors	134
4.5. Revision exercises.	135
4.5.1. Revision of various modeling methods	135
4.5.2. Causality studies and associated modifications	136
4.6. Problem	138
Chapter 5. Dynamic Performance Analysis Tools.	141
5.1. Dynamic performance indicators	142
5.2. Laplace transform and transfer functions	148
5.3. Stability of linear dynamic systems.	158
5.4. Analysis of first- and second-order systems. Model reduction.	167
5.4.1. First-order systems	167
5.4.2. Second-order systems	176
5.4.3. Model reduction.	185
5.5. Revision exercises.	196
5.5.1. Dynamic performances	196
5.5.2. Transfer functions	200
5.5.3. Stability.	202
5.5.4. Model reduction.	205
5.5.5. First-order systems	211
5.5.6. Second-order systems	213

Chapter 6. Mechanical and Electromechanical Power Transmissions	217
6.1. Introduction.	218
6.1.1. Objective.	218
6.1.2. Case study	218
6.2. Variational approaches	220
6.2.1. Variational equivalents of network approaches in mechanics	220
6.2.2. Systems with several degrees of freedom.	223
6.2.3. Multi-domain systems	226
6.3. Modeling by direct integration of local laws: bulk and multi-layer ceramics.	228
6.3.1. Equations of piezoelectricity	228
6.3.2. Equivalent model of piezoelectric ceramics	231
6.3.3. Modelica implementation	233
6.4. Principle of virtual works: amplified actuators	235
6.4.1. Presentation of actuators and modeling hypotheses.	235
6.4.2. Turns ratio	236
6.4.3. Modelica implementation	237
6.5. Energy and co-energy balances: bimetals	239
6.5.1. Presentation of actuators and modeling hypotheses.	239
6.5.2. Modeling.	239
6.6. Lagrange equations: Langevin transducers	242
6.6.1. Actuator presentation	242
6.6.2. Modeling.	243
6.6.3. Modelica implementation	247
6.7. Introductory exercises.	249
6.7.1. Principle of virtual works: scissor mechanism.	249
6.7.2. Energies and co-energies: electromagnetic power-off brakes	250
6.7.3. Lagrange equation: modeling of a personal transporter	253
6.8. Modeling problems	255
6.8.1. Modeling of the mechanical efforts in a car steering system	255
6.8.2. High bandwidth fast steering mirror.	257
Chapter 7. Power Transmission by Low-Compressibility Fluids.	261
7.1. Fluid power.	262
7.1.1. Context	262
7.1.2. Advantages of fluid power use	262
7.2. Presentation of a helicopter actuation system.	263
7.3. Minimal fluid modeling according to the phenomena involved	265
7.3.1. Fluid model requirements	265
7.3.2. Mass density modeling.	267
7.3.3. Modeling of dynamic viscosity.	268

7.3.4. Modeling of the bulk modulus	268
7.3.5. Properties modeling by tables	268
7.4. Modeling of the various physical phenomena.	269
7.4.1. R element	269
7.4.2. C element	270
7.4.3. I element	270
7.5. Modeling of the main hydraulic components	271
7.5.1. Modeling of hydraulic fluid storage	271
7.5.2. Modeling of hydraulic power generation	272
7.5.3. Modeling of the hydraulic power distribution	274
7.5.4. Modeling of hydraulic power modulation	275
7.5.5. Modeling of hydraulic power transformation	277
7.6. Simulation of a helicopter actuation system.	278
7.6.1. Modelica model of an actuation system.	278
7.6.2. Variation of performances depending on temperature	279
7.6.3. Variation of performances depending on antagonist load	281
7.7. Exercises and problems.	282
7.7.1. Multiple-choice questions on the modeling of hydraulic components	282
7.7.2. Problem 1: simple modeling of a hydraulic servo valve	284
7.7.3. Problem 2: modeling of the pressure regulator.	287
Chapter 8. Heat Power Transmission	293
8.1. Heat exchangers	293
8.1.1. Classification of heat exchangers	294
8.1.2. Objectives of the study.	296
8.2. Effectiveness-based thermal modeling of heat exchangers. Constant effectiveness	298
8.3. Estimation of the heat exchanger effectiveness.	302
8.4. Estimation of the global heat transfer coefficient of a heat exchanger .	308
8.5. Estimation of the pressure drops (losses) in the heat exchangers	318
8.6. Revision exercises and problems	322
8.6.1. Sizing of a heat exchanger with concentric tubes	322
8.6.2. Sizing and modeling of a heat exchanger for the recovery of thermal energy in a double flow CMV	323
Chapter 9. Thermal Power Conversion	327
9.1. Several examples of heat engines	328
9.2. Behavior of compressible fluids.	331
9.2.1. Fluid modeling	331
9.2.2. Modeling of thermodynamic processes	334

9.3. Thermodynamics review	335
9.3.1. First law of thermodynamics	335
9.3.2. Thermodynamic cycles	337
9.4. Modeling of the components of heat engines	341
9.4.1. Modeling of a turbine	342
9.4.2. Modeling of a compressor.	345
9.5. Simulation of a thermal power plant	349
9.6. Revision exercises and problems	352
9.6.1. Modeling of fluids	352
9.6.2. Efficiency of a gas turbine	352
9.6.3. Optimization of a gas turbine	354
9.6.4. Simulation of a heat pump	354
References	357
Index	361