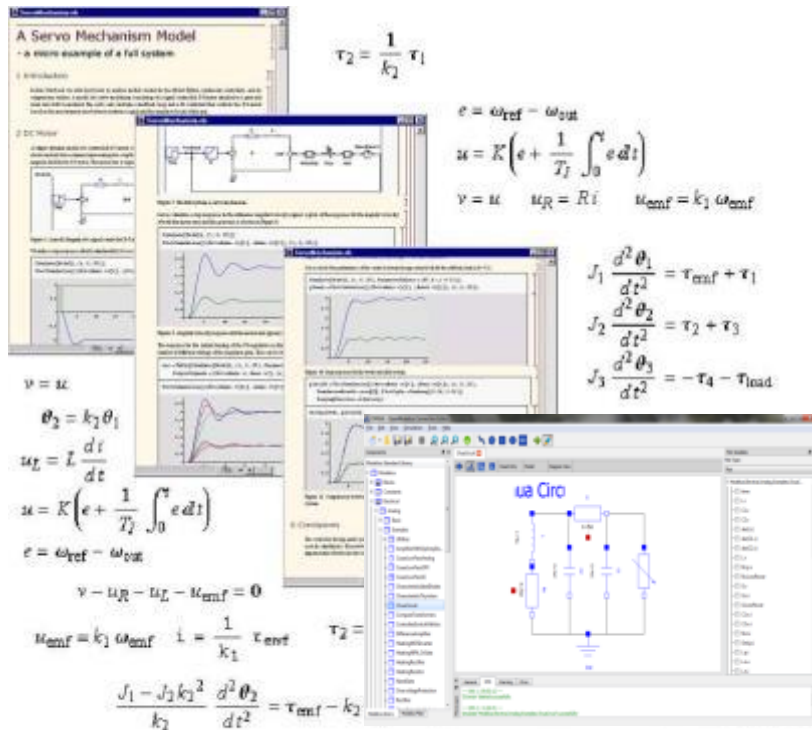


Introduction to Object-Oriented Modeling and Simulation with Modelica and OpenModelica



$\tau_2 = \frac{1}{k_2} \tau_1$

$e = \omega_{\text{ref}} - \omega_{\text{out}}$

$u = K \left(e + \frac{1}{T_I} \int_0^t e \, dt \right)$

$v = u \quad u_R = R i \quad u_{\text{emf}} = k_1 \omega_{\text{emf}}$

$J_1 \frac{d^2 \theta_1}{dt^2} = \tau_{\text{emf}} + \tau_1$

$J_2 \frac{d^2 \theta_2}{dt^2} = \tau_2 + \tau_3$

$J_3 \frac{d^2 \theta_3}{dt^2} = -\tau_4 - \tau_{\text{load}}$

$v = u$

$\theta_2 = k_2 \theta_1$

$u_L = L \frac{di}{dt}$

$u = K \left(e + \frac{1}{T_I} \int_0^t e \, dt \right)$

$e = \omega_{\text{ref}} - \omega_{\text{out}}$

$v - u_R - u_L - u_{\text{emf}} = 0$

$u_{\text{emf}} = k_1 \omega_{\text{emf}} \quad i = \frac{1}{k_1} \tau_{\text{emf}} \quad \tau_2 =$

$\frac{J_1 - J_2 k_2^2}{k_2} \frac{d^2 \theta_2}{dt^2} = \tau_{\text{emf}} - k_2$

Tutorial 2020-02-04

Peter Fritzon

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Research Director at Programming Environments Lab
Vice Director of the Open Source Modelica Consortium
Vice Chairman of Modelica Association

Adrian Pop

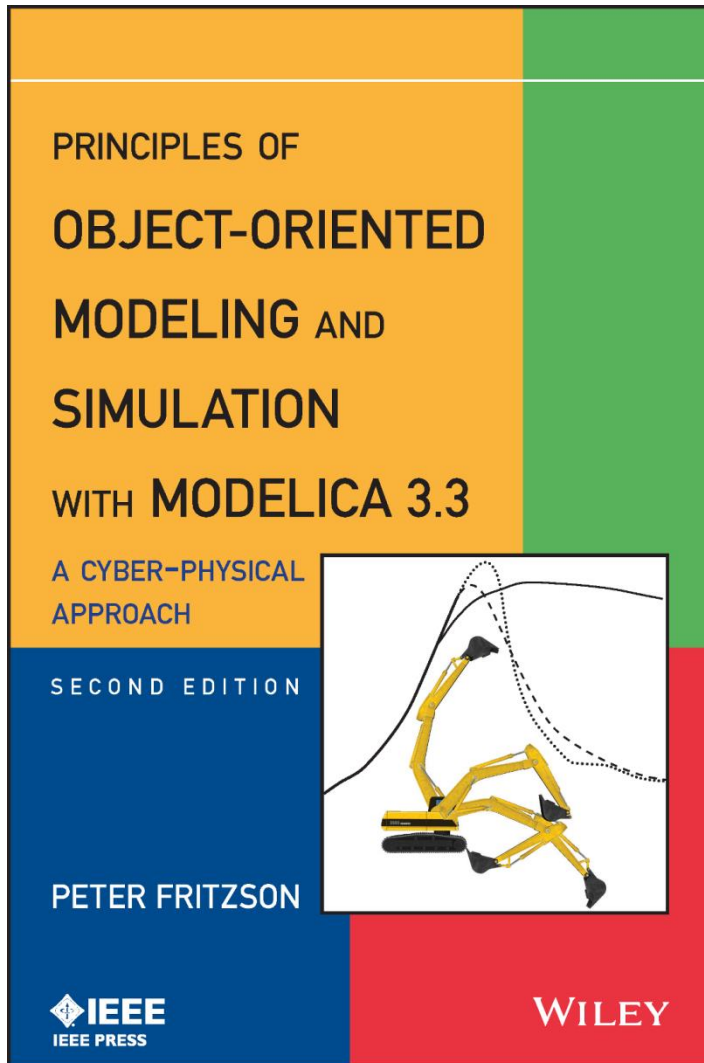
Linköping University, adrian.pop@liu.se
Technical Coordinator of the Open Source Modelica Consortium

Slides

Based on book and lecture notes by Peter Fritzon
Contributions 2004-2005 by Emma Larsdotter Nilsson, Peter Bunus
Contributions 2006-2018 by Adrian Pop and Peter Fritzon
Contributions 2009 by David Broman, Peter Fritzon, Jan Brugård, and Mohsen Torabzadeh-Tari
Contributions 2010 by Peter Fritzon
Contributions 2011 by Peter F., Mohsen T., Adeel Asghar,
Contributions 2012-2018 by Peter Fritzon, Lena Buffoni, Mahder Gebremedhin, Bernhard Thiele, Lennart Ochel
Contributions 2019-2020 by Peter Fritzon, Arunkumar Palanisamy, Bernt Lie, Adrian Pop

Tutorial Based on Book, December 2014

Download OpenModelica Software



Peter Fritzson

Principles of Object Oriented Modeling and Simulation with Modelica 3.3

A Cyber-Physical Approach

Can be ordered from Wiley or Amazon

Wiley-IEEE Press, 2014, 1250 pages

- OpenModelica
 - www.openmodelica.org
- Modelica Association
 - www.modelica.org

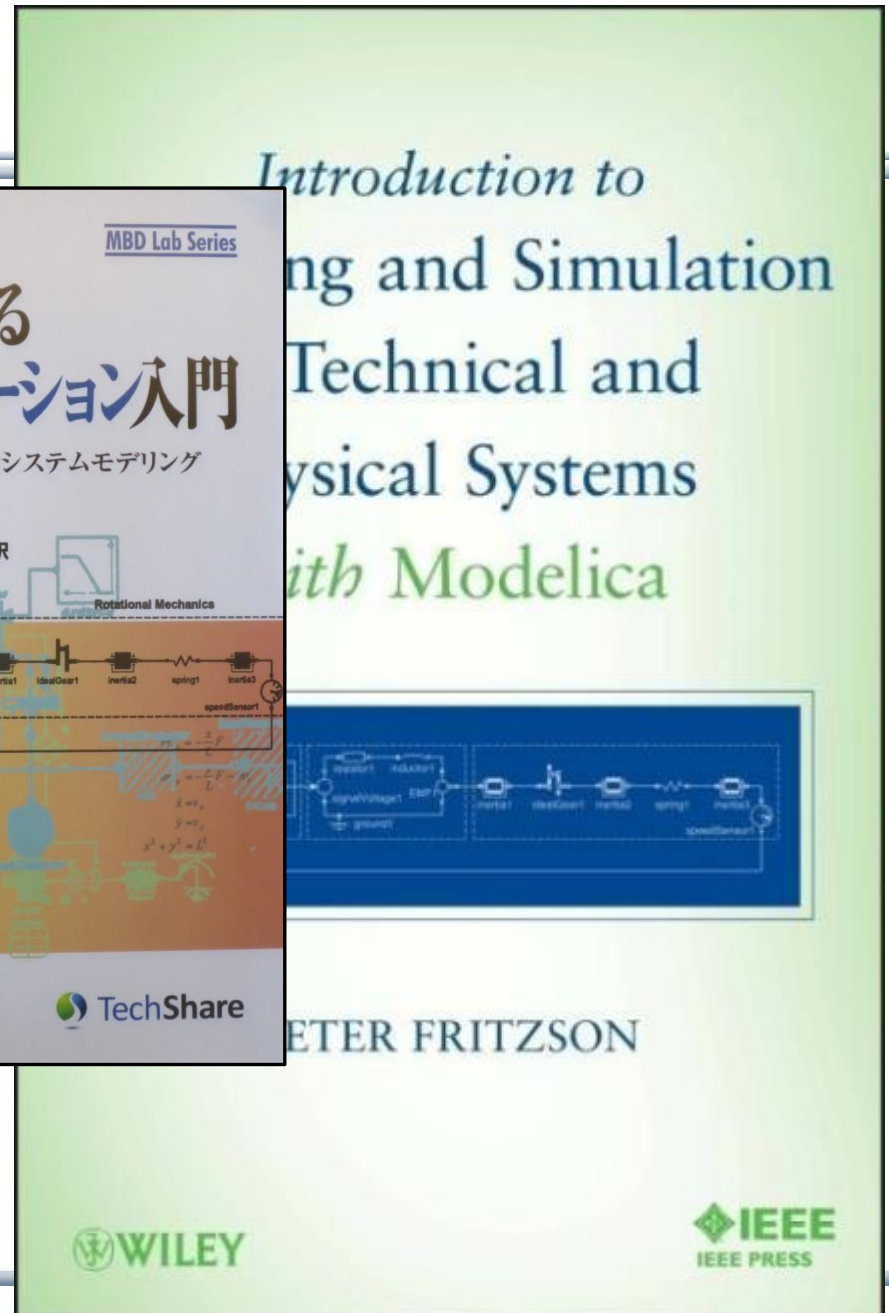
Introductory Modelica Book

September 2011
232 pages

Translations
available in
**Chinese,
Japanese,
Spanish**

**Wiley
IEEE Press**

**For Introductory
Short Courses on
Object Oriented
Mathematical Modeling**



Acknowledgements, Usage, Copyrights

- If you want to use the Powerpoint version of these slides in your own course, send an email to: peter.fritzson@ida.liu.se
- Thanks to Emma Larsdotter Nilsson, Peter Bunus, David Broman, Jan Brugård, Mohsen-Torabzadeh-Tari, Adeel Asghar, Lena Buffoni, for contributions to these slides.
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- Modelica Association: www.modelica.org
- OpenModelica: www.openmodelica.org

Outline

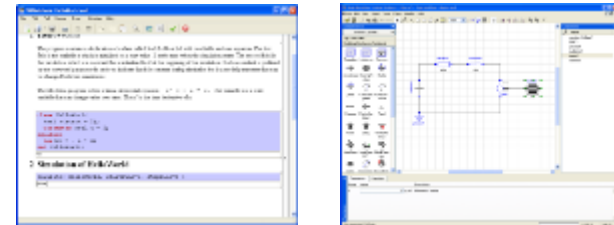
Part I

Introduction to Modelica and a demo example



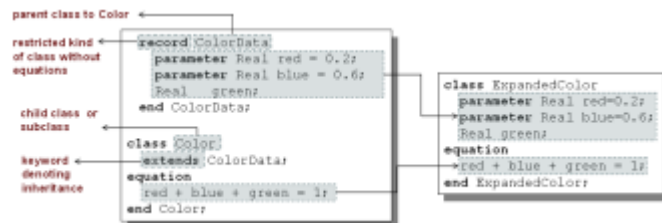
Part II

Modelica environments



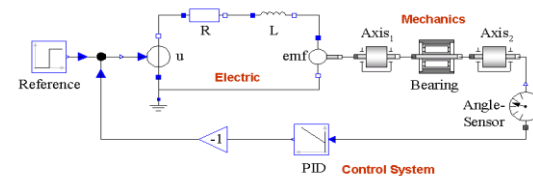
Part III

Modelica language concepts and textual modeling



Part IV

Graphical modeling and the Modelica standard library



Software Installation - Windows

- Start the software installation
- Install OpenModelica-1.16.0 nightly build Download or from the USB Stick (takes about 20min)

Software Installation – Linux (requires internet connection)

- Go to <https://openmodelica.org/index.php/download/download-linux> and follow the instructions.

Software Installation – MAC (requires internet connection)

- Go to <https://openmodelica.org/index.php/download/download-mac> and follow the instructions or follow the instructions written below.
- The installation uses MacPorts. After setting up a MacPorts installation, run the following commands on the terminal (as root):
 - *echo rsync://build.openmodelica.org/macports/ >> /opt/local/etc/macports/sources.conf # assuming you installed into /opt/local*
 - *port selfupdate*
 - *port install openmodelica-devel*

Software Installation for OMSens – Python Anaconda

USB INSTALLATION

This is **only needed for Sensitivity analysis feature**

Install **Anaconda3.exe** from USB stick (**Windows 64 bit**)
(takes about 20 min)

For other platforms, download from
Anaconda : <https://www.anaconda.com/distribution/>

Part I

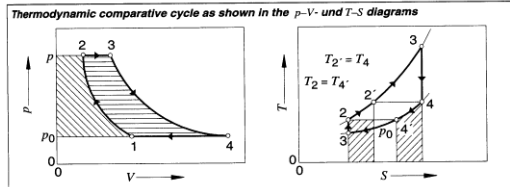
Introduction to Modelica and a demo example



Modelica Background: Stored Knowledge

Model knowledge is stored in books and human minds which computers cannot access

Internal-combustion engines 417



from T_2 to T_2' , supplied by the heat exchanger is coupled with a thermal discharge ($4 \rightarrow 4'$). If heat is completely exchanged, the quantity of heat to be added per unit of gas is reduced to

$$q_{in} = c_p \cdot (T_3 - T_2) = c_p \cdot (T_3 - T_4)$$

and the quantity of heat to be removed is

$$q_{out} = c_p \cdot (T_4 - T_1) = c_p \cdot (T_2 - T_1).$$

The maximum thermal efficiency for the gas turbine with heat exchanger is:

$$\eta_{th} = 1 - Q_{out}/Q_{in} = 1 - (T_2 - T_1)/(T_3 - T_4)$$

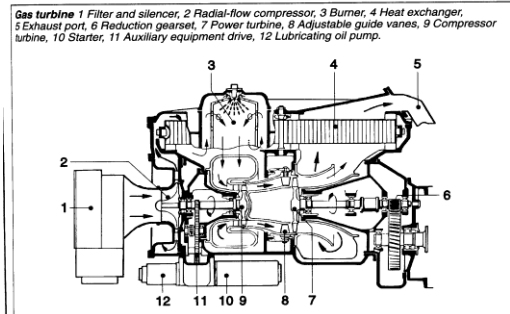
Where $p_2/p_1 = (T_2/T_1)^{\frac{\gamma-1}{\gamma}} = (T_3/T_4)^{\frac{\gamma-1}{\gamma}}$ and $T_4 = T_3 \cdot (T_1/T_2)$ thus

$$\eta_{th} = 1 - (T_2/T_3)$$

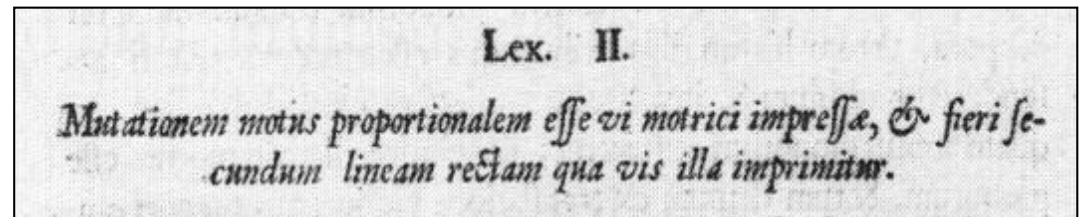
Current gas-turbine powerplants achieve thermal efficiencies of up to 35%.

Advantages of the gas turbines: clean exhaust without supplementary emissions-control devices; extremely smooth running; multifuel capability; good static torque curve; extended maintenance intervals.

Disadvantages: manufacturing costs still high; poor transitional response; higher fuel consumption; less suitable for low-power applications.

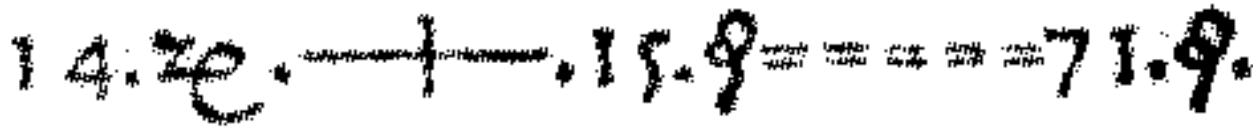


“The change of motion is proportional to the motive force impressed”
– Newton



Modelica Background: The Form – Equations

- Equations were used in the third millennium B.C.
- Equality sign was introduced by Robert Recorde in 1557



Newton still wrote text (Principia, vol. 1, 1686)

“The change of motion is proportional to the motive force impressed”

CSSL (1967) introduced a special form of “equation”:

variable = expression

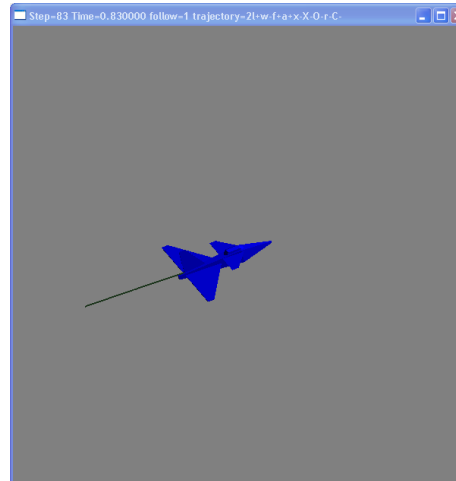
$v = \text{INTEG}(F) / m$

Programming languages usually do not allow equations!

What is Modelica?

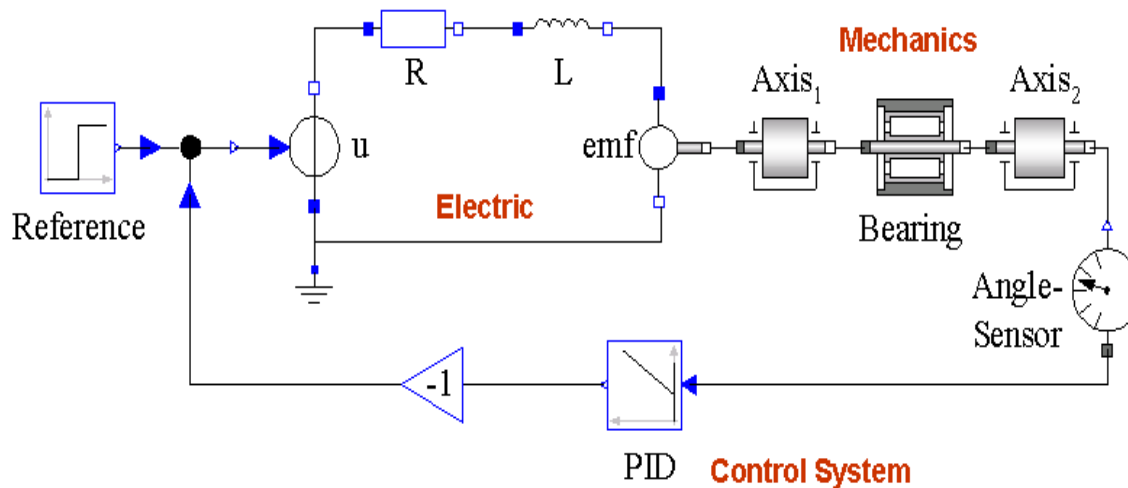
A language for modeling of **complex cyber-physical systems**

- Robotics
- Automotive
- Aircrafts
- Satellites
- Power plants
- Systems biology



What is Modelica?

A language for modeling of complex cyber-physical systems



Primary designed for **simulation**, but there are also other usages of models, e.g. optimization.

What is Modelica?

A language for modeling of complex cyber-physical systems

i.e., Modelica is not a tool

Free, open language
specification:



There exist one free and several commercial tools, for example:

- **OpenModelica from OSMC**
(in ABB Optimax, Bosch-Rexr Control Edge Designer, Mike DHI)
- Dymola from Dassault systems
- Wolfram System Modeler from Wolfram MathCore
- SimulationX from ITI, part of ESI Group
- MapleSim from MapleSoft
(also in Altair solidThinking Activate)
- AMESIM from LMS
- Optimica Toolkit from Modelon
(also in ANSYS Simpler, etc.)
- MWORKS from Tongyang Sw & Control
- IDA Simulation Env, from Equa

Available at: www.modelica.org

*Developed and standardized
by Modelica Association*

Modelica – The Next Generation Modeling Language

Declarative statically typed language

Equations and mathematical functions allow acausal modeling, high level specification and static type checking for increased correctness

Multi-domain modeling

Combine electrical, mechanical, thermodynamic, hydraulic, biological, control, event, real-time, etc...

Everything is a class

Safe engineering practices by statically typed object-oriented language, general class concept, Java & MATLAB-like syntax

Visual component programming

Hierarchical system architecture capabilities

Efficient, non-proprietary

Efficiency comparable to C; advanced equation compilation, e.g. 300 000 equations, ~150 000 lines on standard PC

Modelica Acausal Modeling

What is *acausal* modeling/design?

Why does it increase *reuse*?

The acausality makes Modelica library classes *more reusable* than traditional classes containing assignment statements where the input-output causality is fixed.

Example: a resistor *equation*:

$$\mathbf{R} * \mathbf{i} = \mathbf{v};$$

can be used in three ways:

$$\mathbf{i} := \mathbf{v} / \mathbf{R};$$

$$\mathbf{v} := \mathbf{R} * \mathbf{i};$$

$$\mathbf{R} := \mathbf{v} / \mathbf{i};$$

What is Special about Modelica?

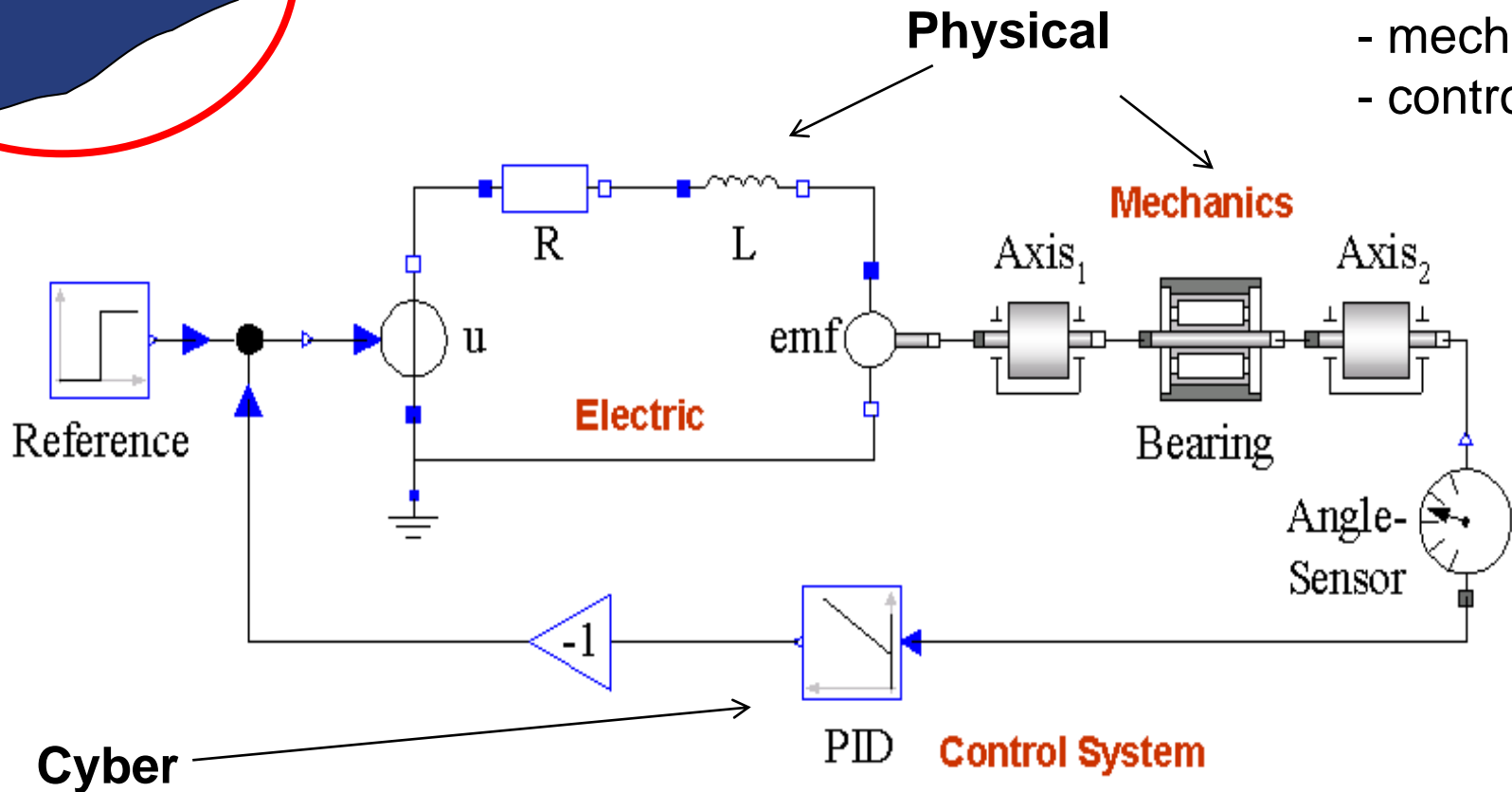
- Multi-Domain Modeling
- Visual acausal hierarchical component modeling
- Typed declarative equation-based textual language
- Hybrid modeling and simulation

What is Special about Modelica?

Multi-Domain
Modeling

Cyber-Physical Modeling

- 3 domains
- electric
 - mechanics
 - control



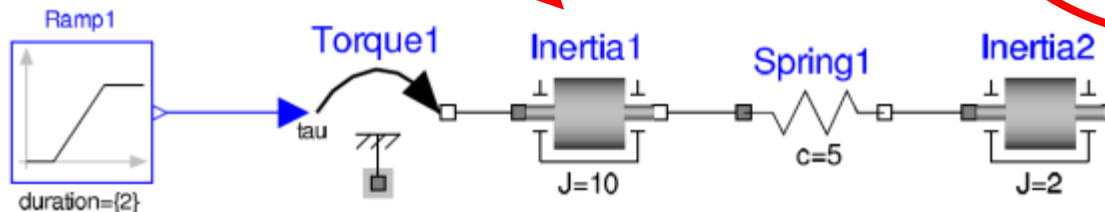
What is Special about Modelica?

Multi-Domain
Modeling

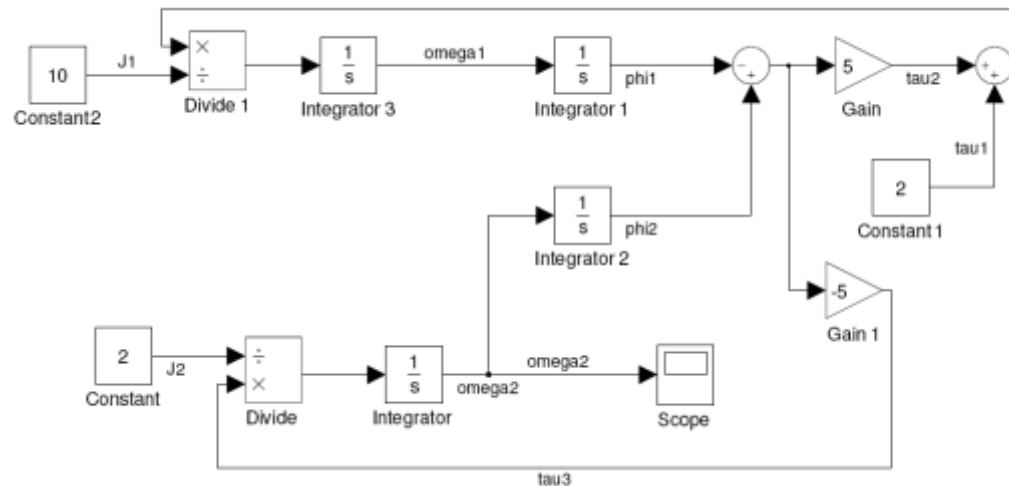
Visual Acausal
Hierarchical
Component
Modeling

Keeps the physical
structure

Acausal model
(Modelica)



Causal
block-based
model
(Simulink)

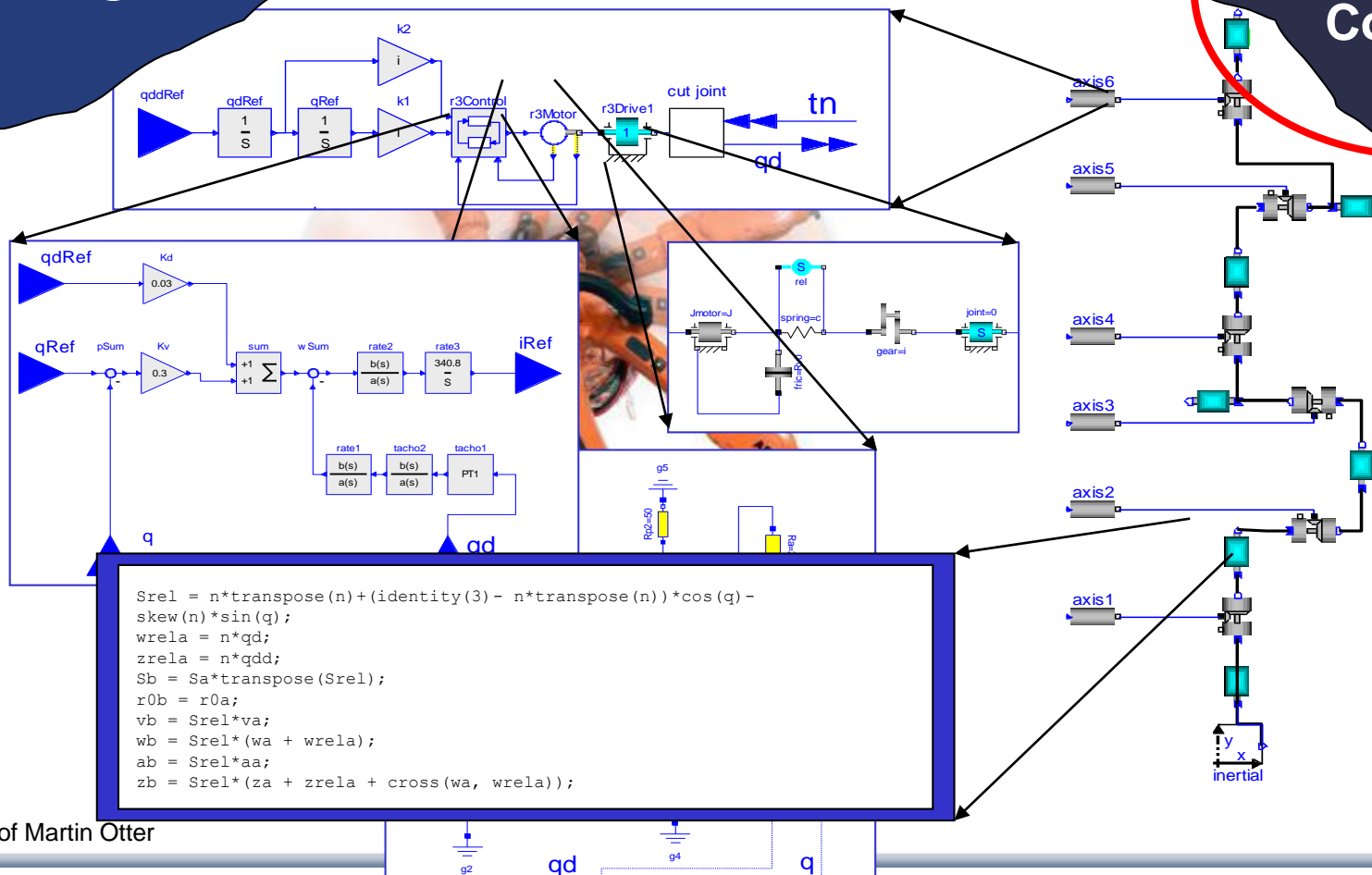


What is Special about Modelica?

Multi-Domain
Modeling

Hierarchical system
modeling

Visual Acausal
Hierarchical
Component
Modeling



Courtesy of Martin Otter

What is Special about Modelica?

Multi-Domain
Modeling

A textual *class-based* language
OO primary used for as a structuring concept

Visual Acausal
Hierarchical
Component
Modeling

Behaviour described declaratively using

- Differential algebraic equations (DAE) (continuous-time)
- Event triggers (discrete-time)

Variable
declarations

```
class VanDerPol "Van der Pol oscillator model"  
  Real x(start = 1) "Descriptive string for x";  
  Real y(start = 1) "y coordinate";  
  parameter Real lambda = 0.3;  
equation  
  der(x) = y;  
  der(y) = -x + lambda*(1 - x*x)*y;  
end VanDerPol;
```

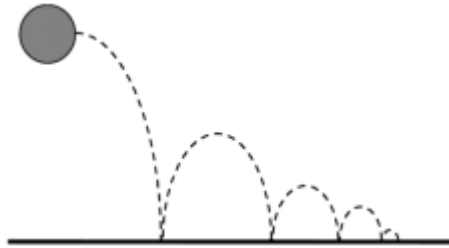
Differential equations

Typed
Declarative
Equation-based
Textual Language

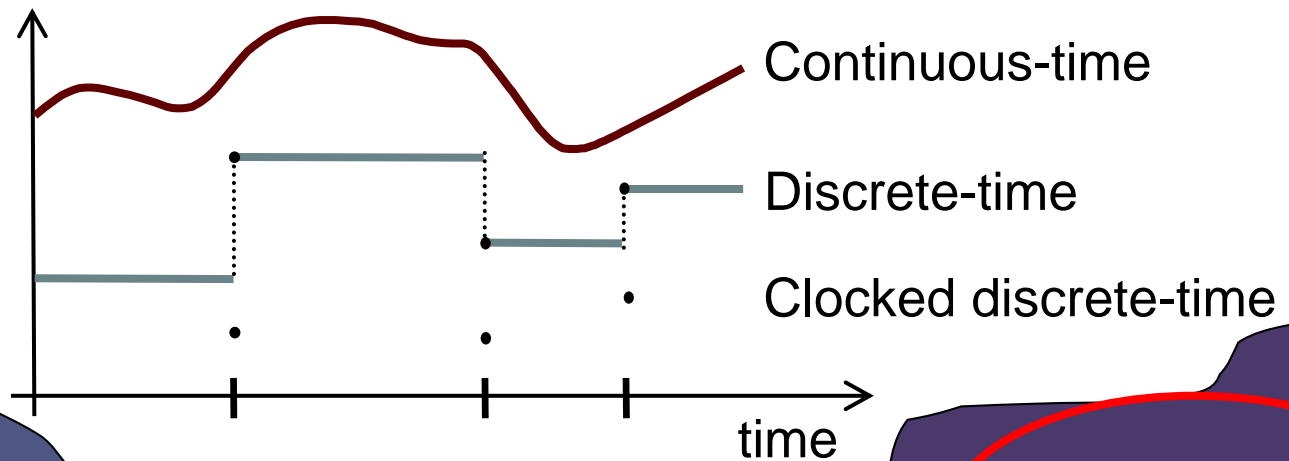
What is Special about Modelica?

Multi-Domain
Modeling

Visual Acausal
Component
Modeling



Hybrid modeling =
continuous-time + discrete-time modeling

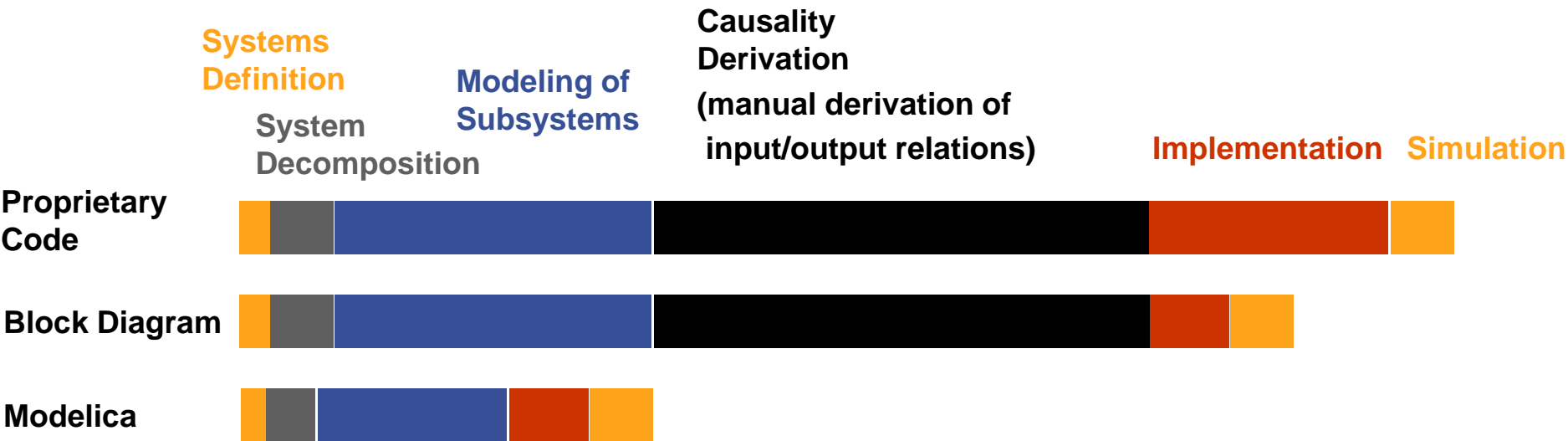


Typed
Declarative
Equation-based
Textual Language

Hybrid
Modeling

Modelica – Faster Development, Lower Maintenance than with Traditional Tools

Block Diagram (e.g. Simulink, ...) or
 Proprietary Code (e.g. Ada, Fortran, C,...)
 vs Modelica

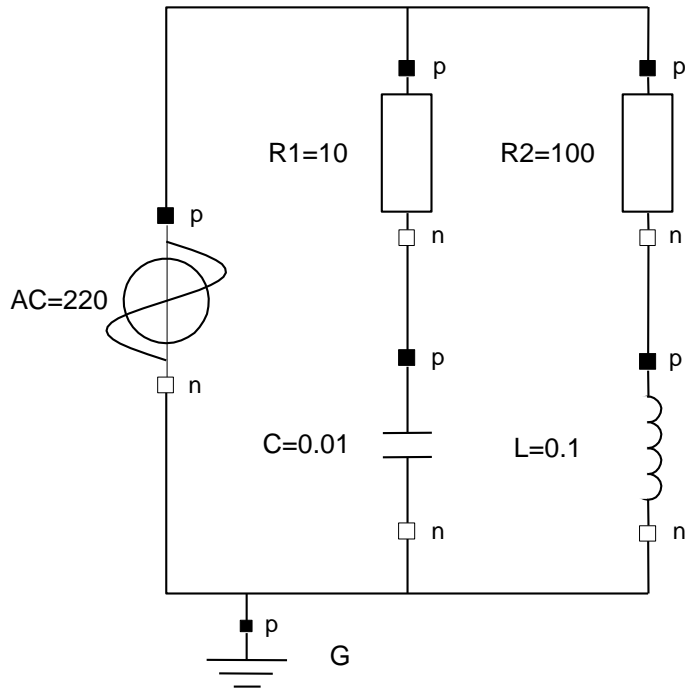


Modelica vs Simulink Block Oriented Modeling

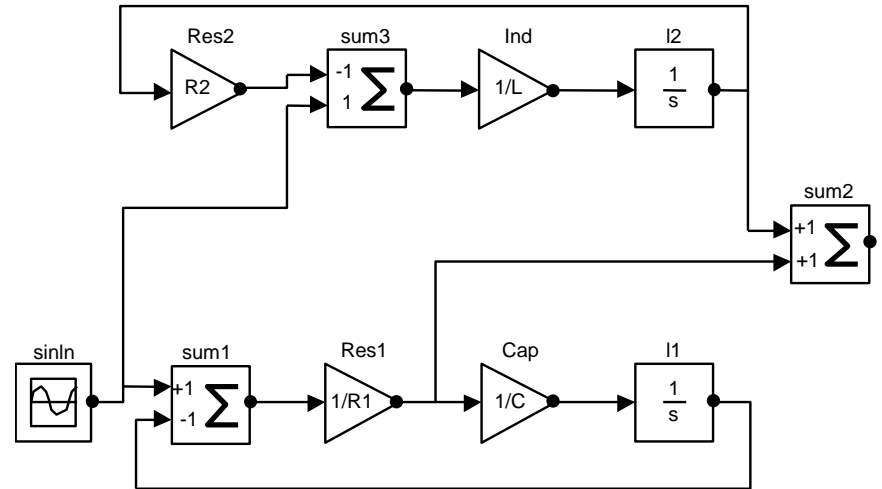
Simple Electrical Model

Modelica:
Physical model –
easy to understand

Keeps the
physical
structure



Simulink:
Signal-flow model – hard to
understand



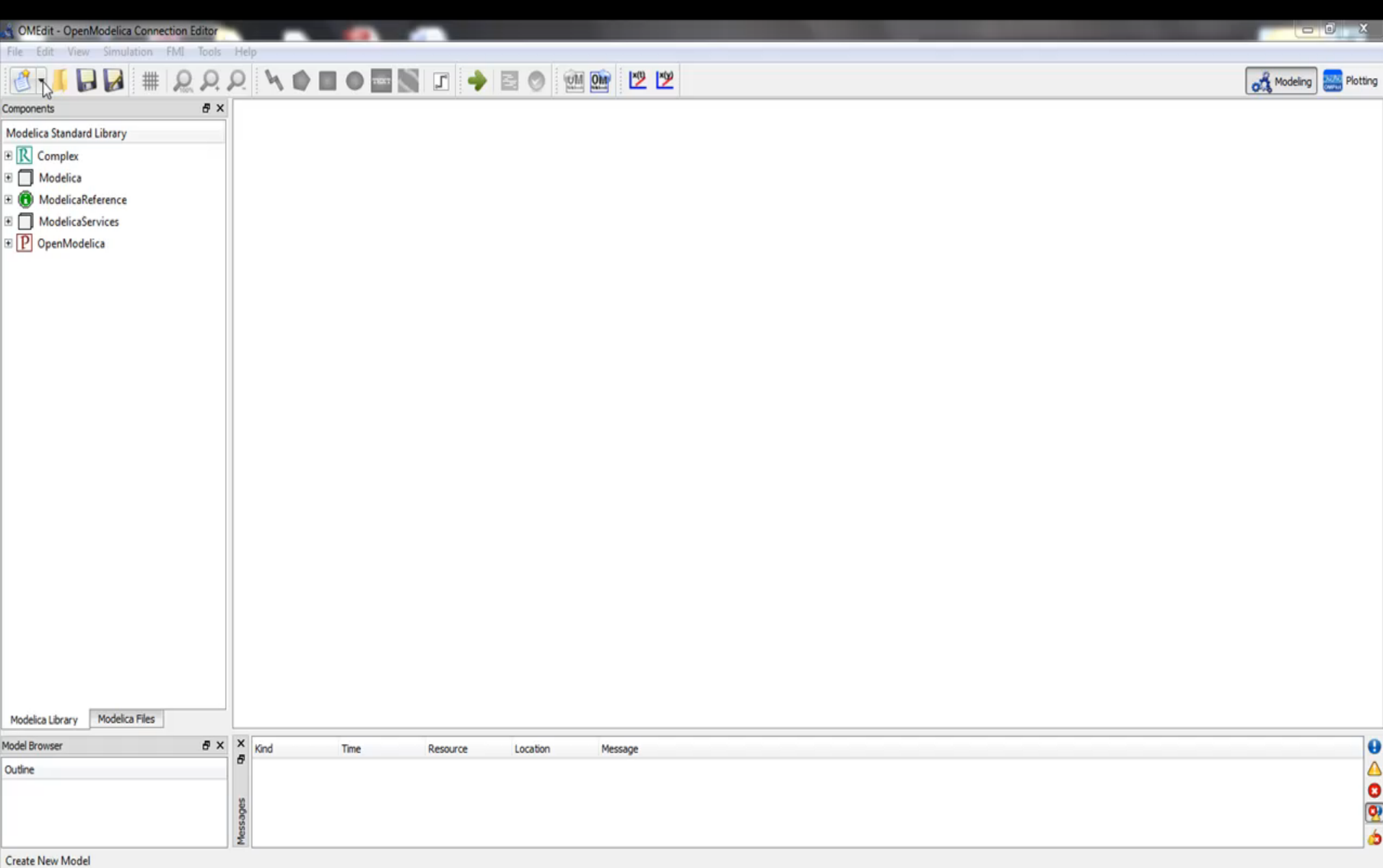
Graphical Modeling - Using Drag and Drop Composition

The screenshot displays the OpenModelica Connection Editor (OMEdit) interface. The main window shows a circuit diagram titled "RL_Circuit*" in "Diagram View". The circuit consists of a sine voltage source labeled "sineVoltage1" connected in series with a resistor labeled "resistor1" (with the equation $R = \%R$) and an inductor labeled "inductor1" (with the equation $L = \%L$). The circuit is completed by a ground reference labeled "ground1".

On the left side, the "Components" pane shows the "Modelica Standard Library" tree structure, including "Electrical" > "Analog" > "Sources". The "Messages" pane at the bottom right shows the following log entries:

```
--- Info 3 : 10:39:17 ---  
Connected: (resistor1.n, inductor1.p)  
--- Info 4 : 10:39:39 ---  
Connected: (inductor1.n, sineVoltage1.n)
```

Graphical Modeling with OpenModelica Environment



Multi-Domain (Electro-Mechanical) Modelica Model

- A DC motor can be thought of as an electrical circuit which also contains an electromechanical component

model DCMotor

```
Resistor R(R=100);
```

```
Inductor L(L=100);
```

```
VsourceDC DC(f=10);
```

```
Ground G;
```

```
ElectroMechanicalElement EM(k=10, J=10, b=2);
```

```
Inertia load;
```

equation

```
connect (DC.p, R.n);
```

```
connect (R.p, L.n);
```

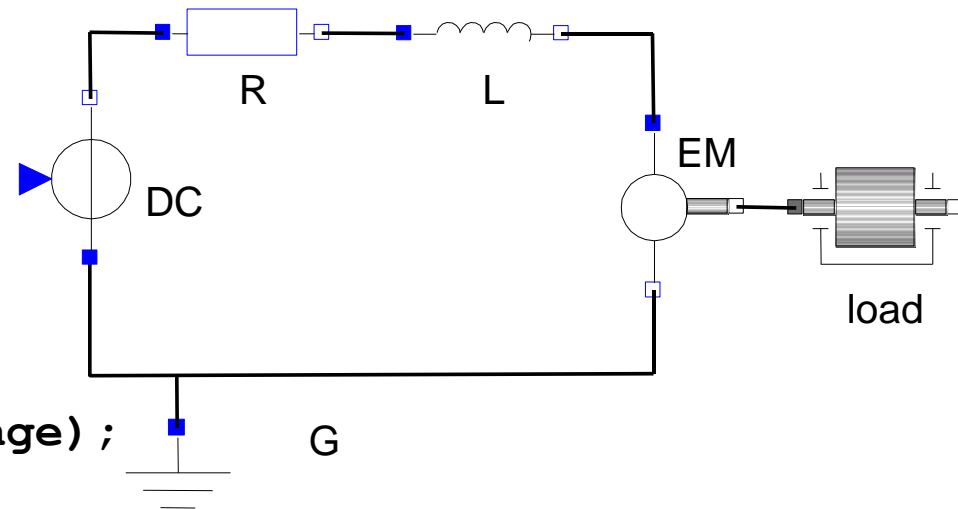
```
connect (L.p, EM.n);
```

```
connect (EM.p, DC.n);
```

```
connect (DC.n, G.p);
```

```
connect (EM.flange, load.flange);
```

end DCMotor



Corresponding DCMotor Model Equations

The following equations are automatically derived from the Modelica model:

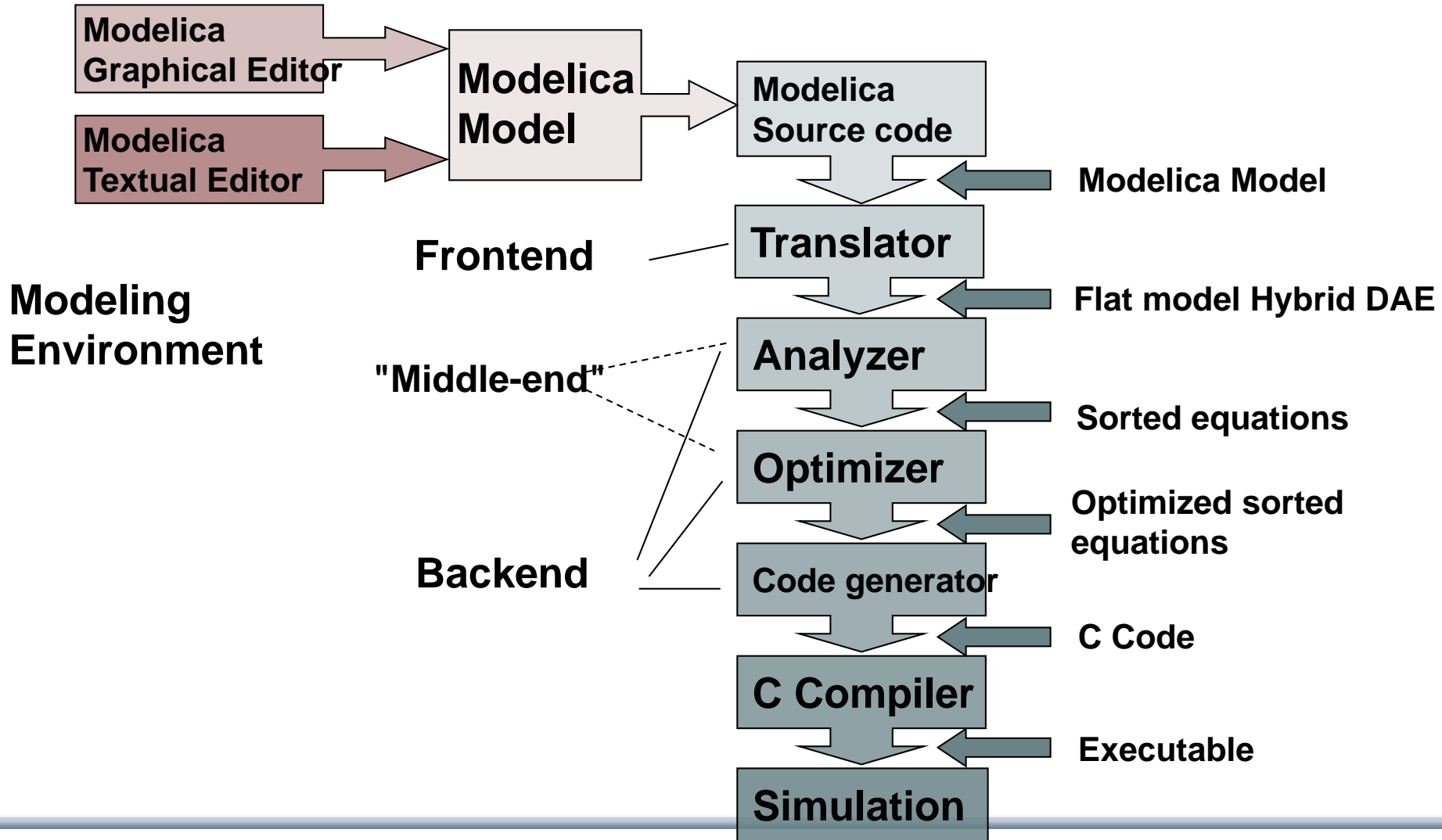
| | | |
|------------------------|---|------------------------|
| $0 == DC.p.i + R.n.i$ | $EM.u == EM.p.v - EM.n.v$ | $R.u == R.p.v - R.n.v$ |
| $DC.p.v == R.n.v$ | $0 == EM.p.i + EM.n.i$ | $0 == R.p.i + R.n.i$ |
| | $EM.i == EM.p.i$ | $R.i == R.p.i$ |
| $0 == R.p.i + L.n.i$ | $EM.u == EM.k * EM.\omega$ | $R.u == R.R * R.i$ |
| $R.p.v == L.n.v$ | $EM.i == EM.M / EM.k$ | |
| | $EM.J * EM.\omega == EM.M - EM.b * EM.\omega$ | $L.u == L.p.v - L.n.v$ |
| $0 == L.p.i + EM.n.i$ | | $0 == L.p.i + L.n.i$ |
| $L.p.v == EM.n.v$ | $DC.u == DC.p.v - DC.n.v$ | $L.i == L.p.i$ |
| | $0 == DC.p.i + DC.n.i$ | $L.u == L.L * L.i'$ |
| $0 == EM.p.i + DC.n.i$ | $DC.i == DC.p.i$ | |
| $EM.p.v == DC.n.v$ | $DC.u == DC.Amp * Sin[2 \pi DC.f * t]$ | |
| $0 == DC.n.i + G.p.i$ | | |
| $DC.n.v == G.p.v$ | | |

(load component not included)

Automatic transformation to ODE or DAE for simulation:

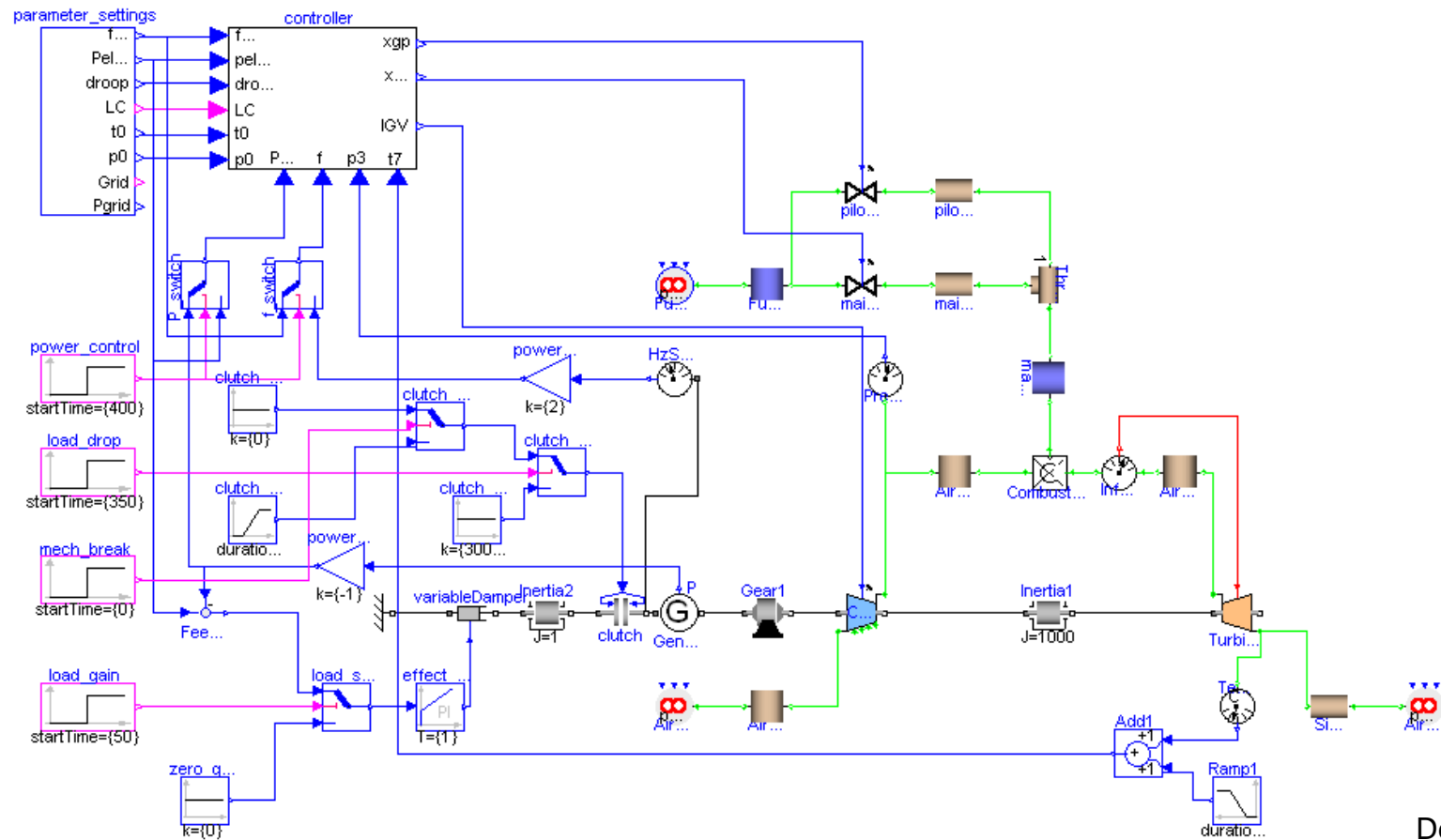
$$\frac{dx}{dt} == f[x, u, t] \quad g\left[\frac{dx}{dt}, x, u, t\right] == 0$$

Model Translation Process to Hybrid DAE to Code



Modelica in Power Generation

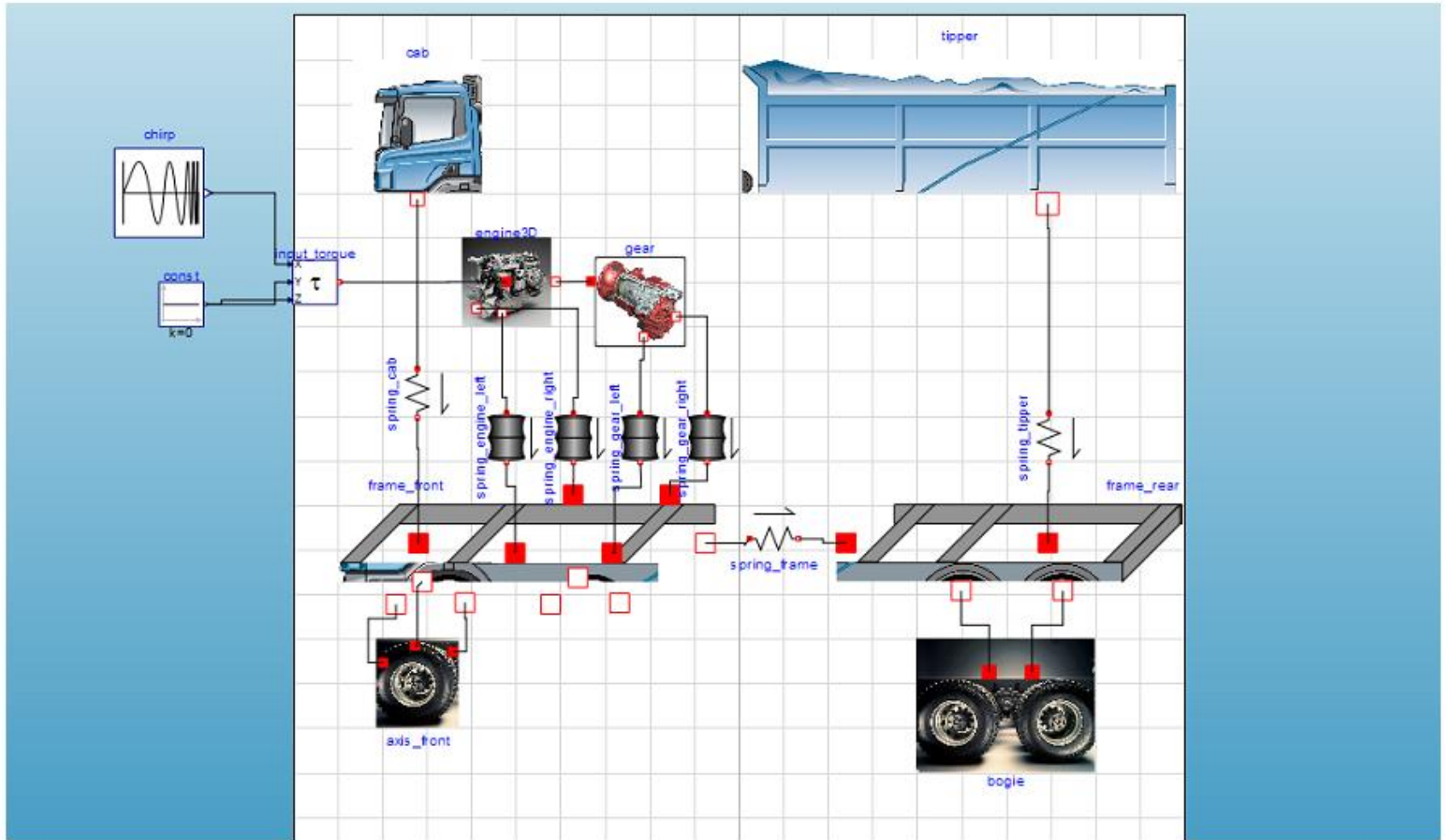
GTX Gas Turbine Power Cutoff Mechanism



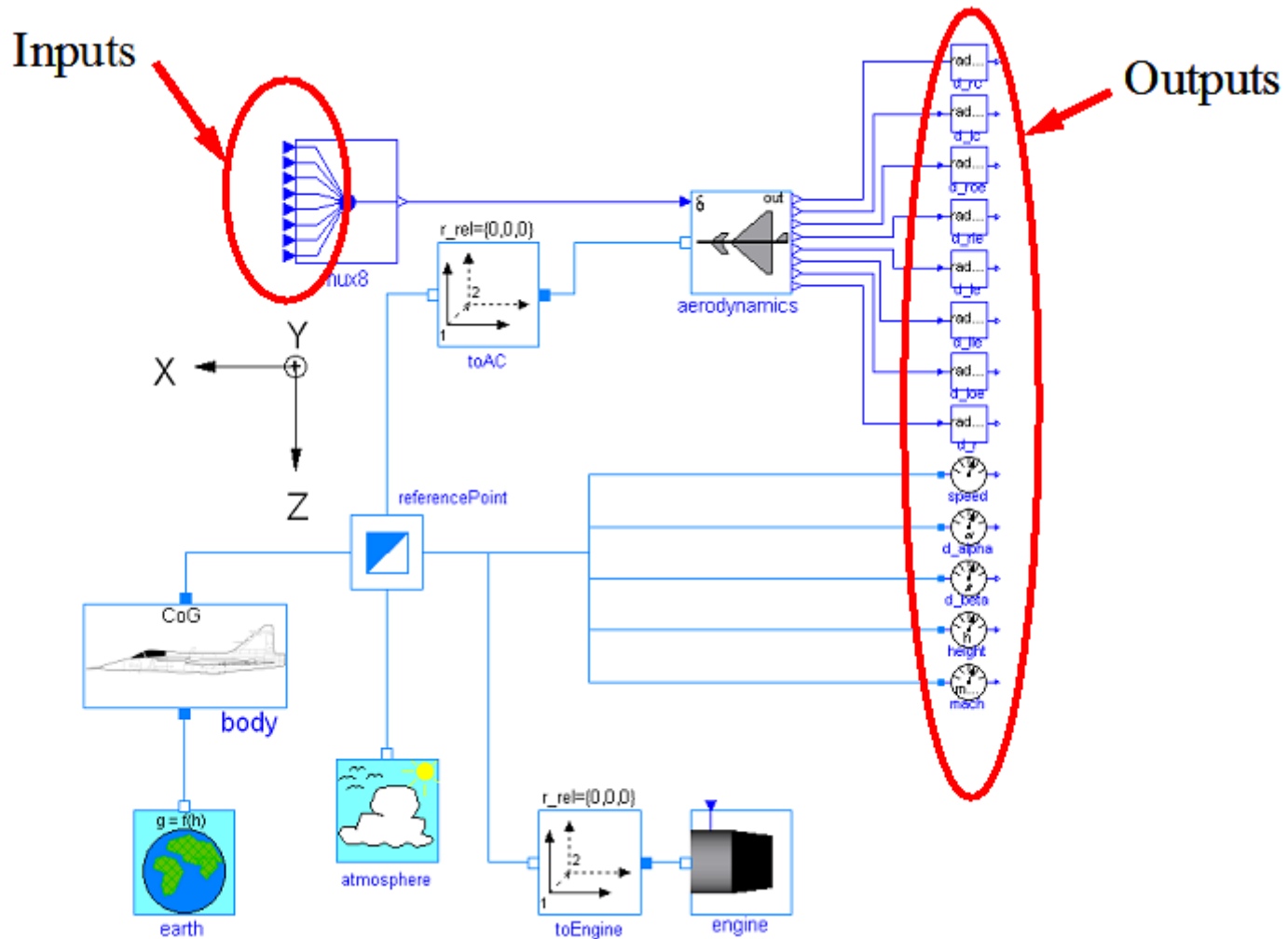
Developed
by MathCore
for Siemens

Courtesy of Siemens Industrial Turbomachinery AB

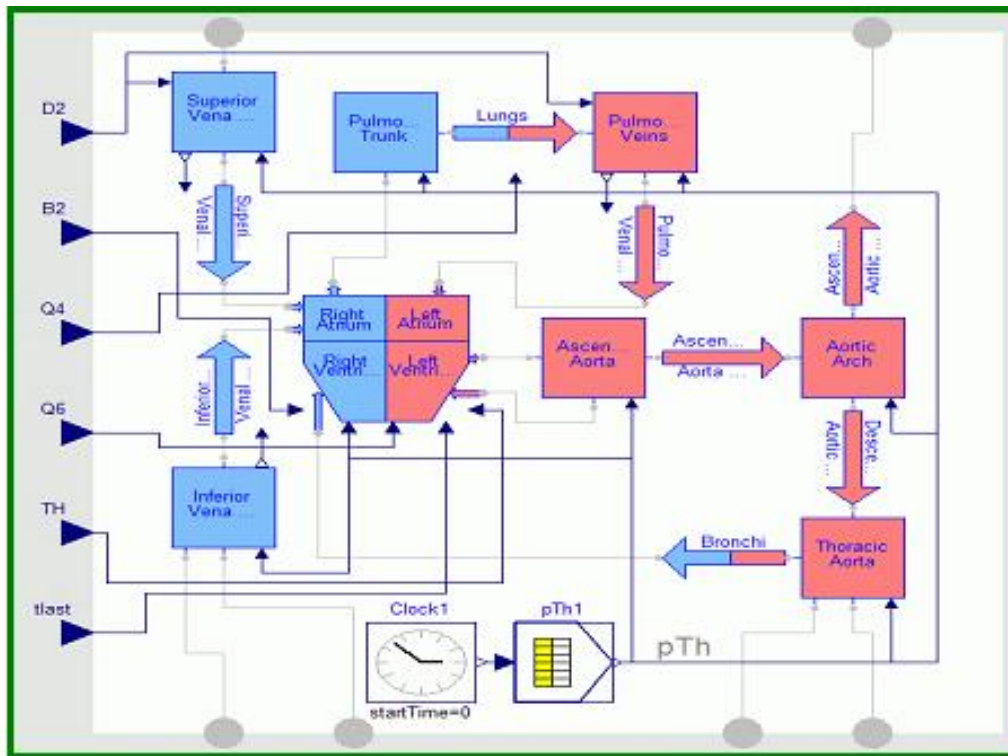
Modelica in Automotive Industry



Modelica in Avionics



Modelica in Biomechanics



Application of Modelica in Robotics Models

Real-time Training Simulator for Flight, Driving

- Using Modelica models generating real-time code
- Different simulation environments (e.g. Flight, Car Driving, Helicopter)
- Developed at DLR Munich, Germany
- Dymola Modelica tool

(Movie demo next page)



Courtesy of Tobias Bellmann, DLR,
Oberpfaffenhofen, Germany

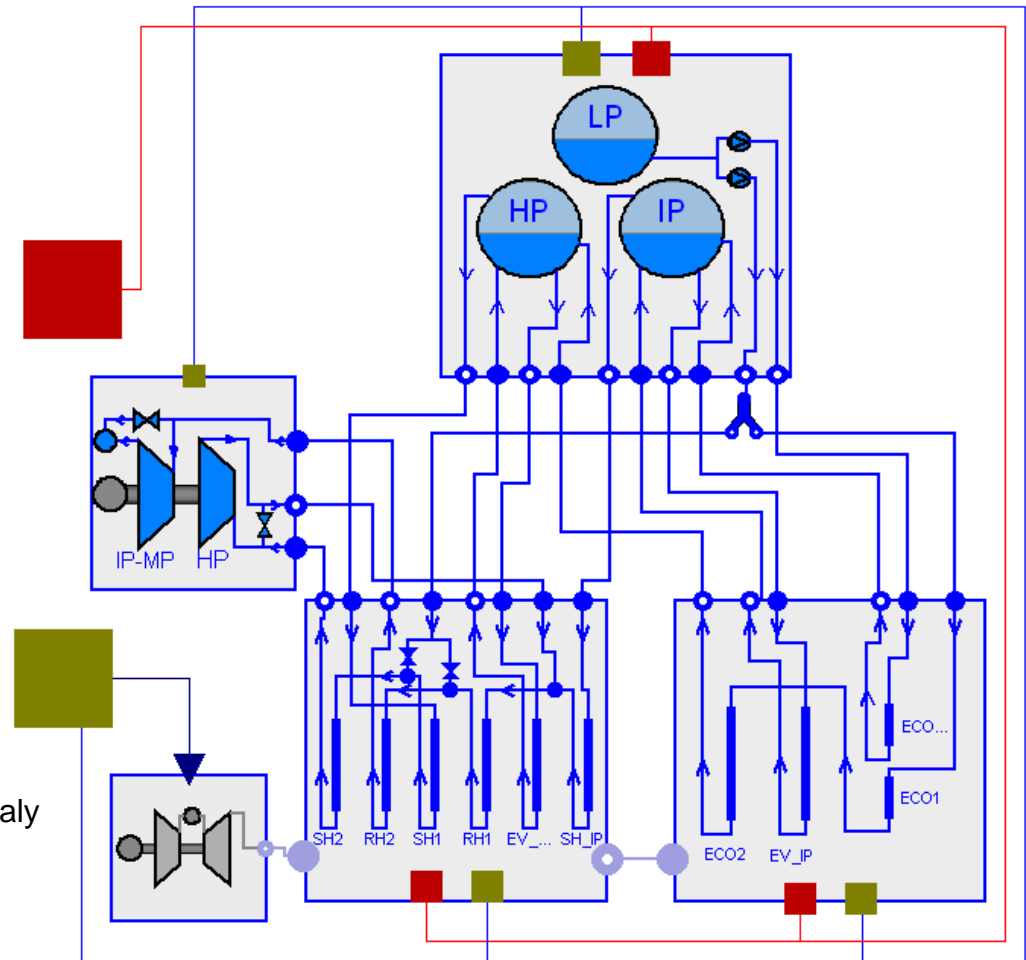
DLR Real-time Training Simulator Movie Demo



Combined-Cycle Power Plant

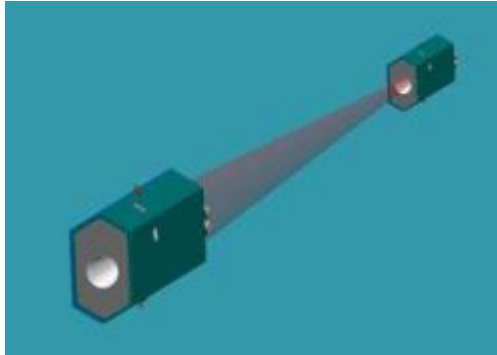
Plant model – system level

- GT unit, ST unit, Drum boilers unit and HRSG units, connected by thermo-fluid ports and by signal buses
- Low-temperature parts (condenser, feedwater system, LP circuits) are represented by trivial boundary conditions.
- GT model: simple law relating the electrical load request with the exhaust gas temperature and flow rate.



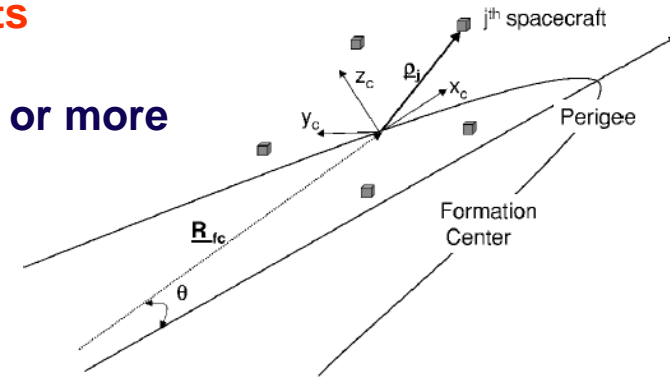
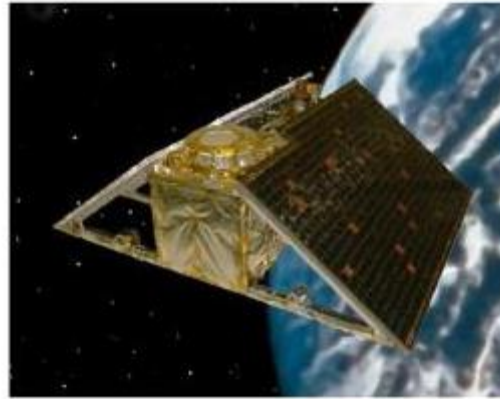
Courtesy Francesco Casella, Politecnico di Milano – Italy
and Francesco Pretolani, CESI SpA - Italy

Modelica Spacecraft Dynamics Library



Formation flying on elliptical orbits

Control the relative motion of two or more spacecraft



Attitude control for satellites using magnetic coils as actuators

Torque generation mechanism: interaction between coils and geomagnetic field

Courtesy of Francesco Casella, Politecnico di Milano, Italy



Large-scale ABB OpenModelica Application

Generate code for controlling 7.5 to 10% of German Power Production



ABB OPTIMAX PowerFit

- Real-time optimizing control of large-scale virtual power plant for system integration
- **Software including OpenModelica** now used in managing more than 2500 renewable plants, total up to 1.5 GW

High scalability supporting growth

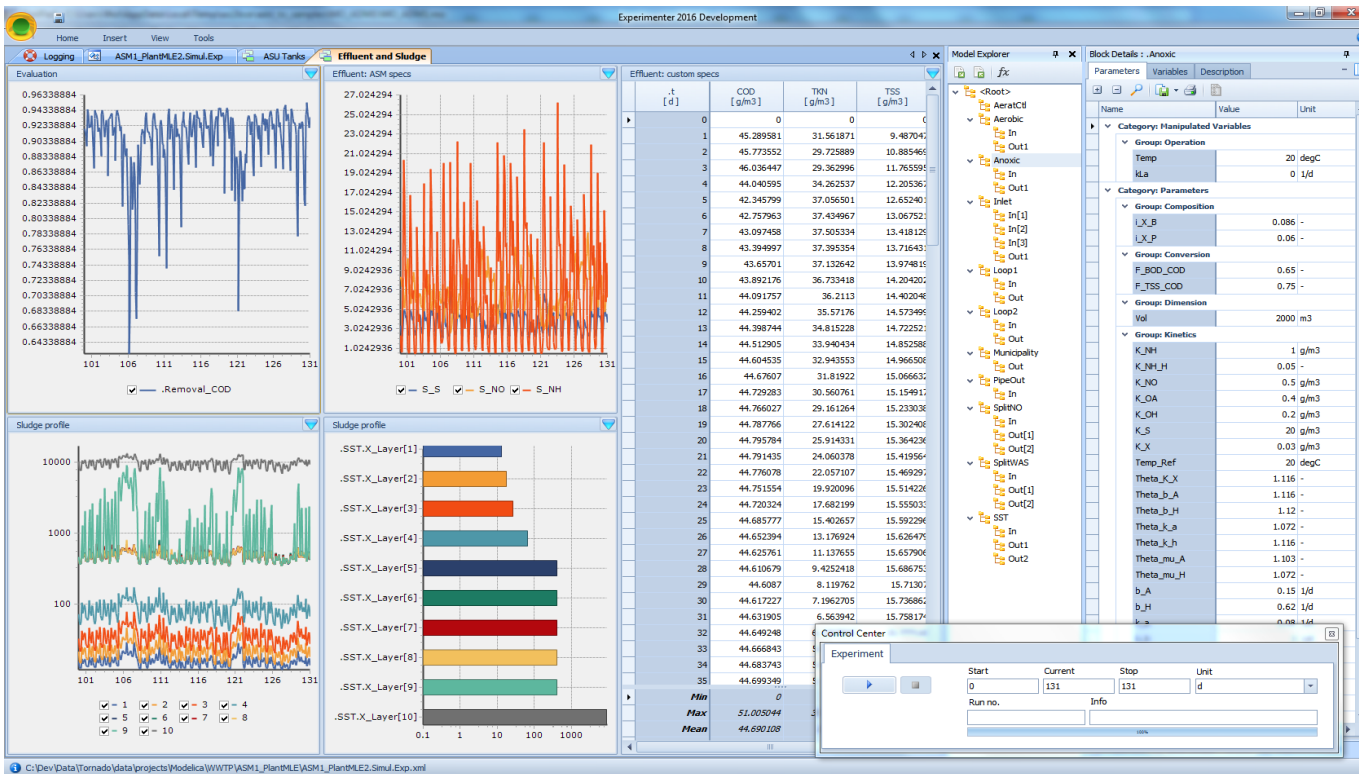
- 2012: initial delivery (for 50 plants)
- 2013: SW extension (500 plants)
- 2014: HW+SW extension (> 2000)
- 2015: HW+SW extension, incl. OpenModelica generating optimizing controller code in FMI 2.0 form

Manage 7.5% - 10% of German Power

- 2015, Aug: OpenModelica Exports FMUs for real-time optimizing control (seconds) of about **5.000 MW (7.5%) of power in Germany**

Industrial Product with OEM Usage of OpenModelica – MIKE by DHI, WEST Water Quality, Water Treatment and Sludge

- MIKE by DHI, www.mikebydhi.com, WEST Water Quality modeling and simulation environment
- Includes a large part of the OpenModelica compiler using the OEM license.
- Here a water treatment effluent and sludge simulation.

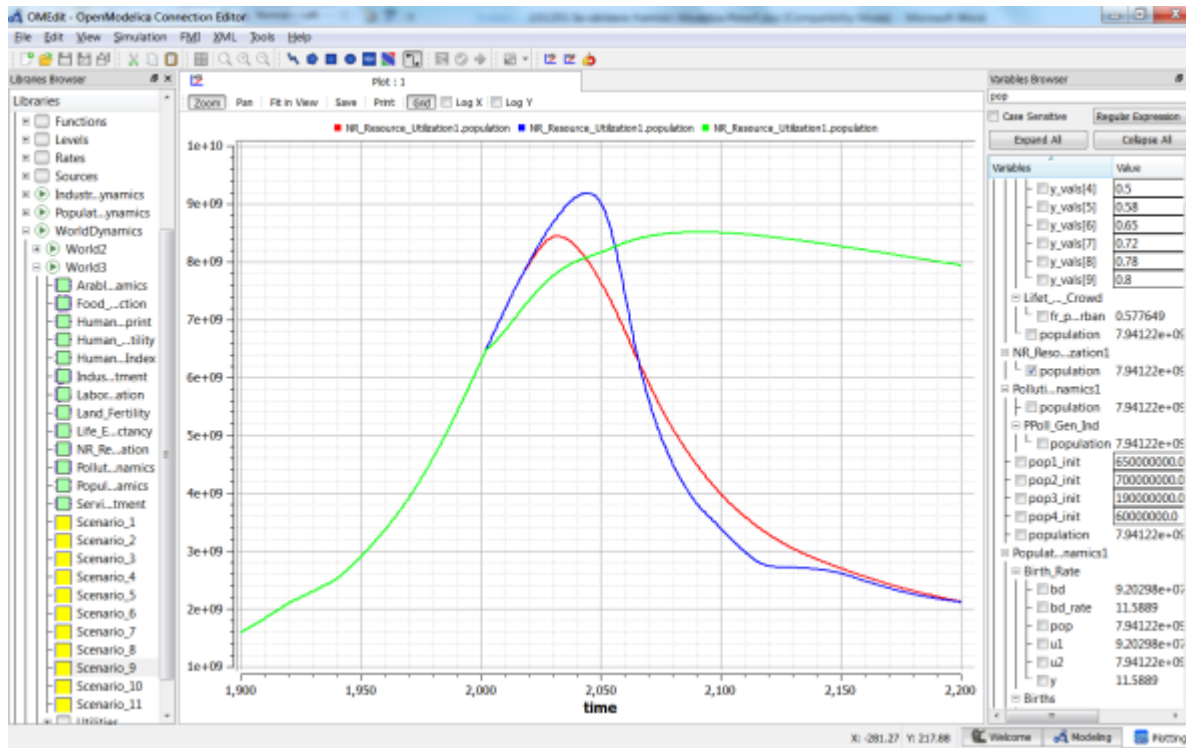


**Most important challenge
for humanity -
Develop a sustainable society!**

**Use Modelica in to model and optimize
sustainable technical innovations,
and a sustainable circular economy**

System Dynamics – World Society Simulation

Limits to Material Growth; Population, Energy and Material flows



Left. World3 simulation with OpenModelica

- 2 collapse scenarios (close to current developments)
- 1 sustainable scenario (green).

CO2 Emissions per person:

- USA 17 ton/yr
- Sweden 7 ton/yr
- India 1.4 ton/yr
- Bangladesh 0.3 ton/yr

- System Dynamics Modelica library by Francois Cellier (ETH), et al in OM distribution.
- Warming converts many agriculture areas to deserts (USA, Europe, India, Amazonas)
- Ecological breakdown around 2080-2100, drastic reduction of world population
- To **avoid** this: Need for massive investments in sustainable technology and renewable energy sources

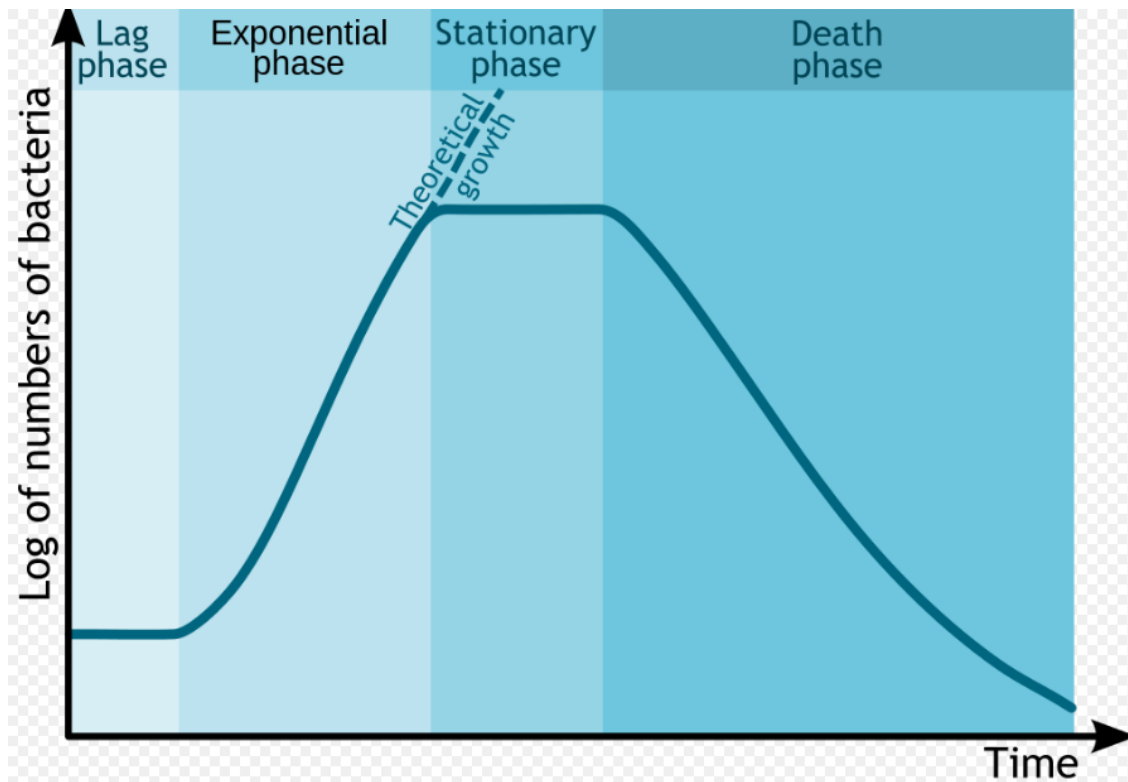
Are Humans More Intelligent than Bacteria?

Not yet evident!

Humans
on a
finite
Earth

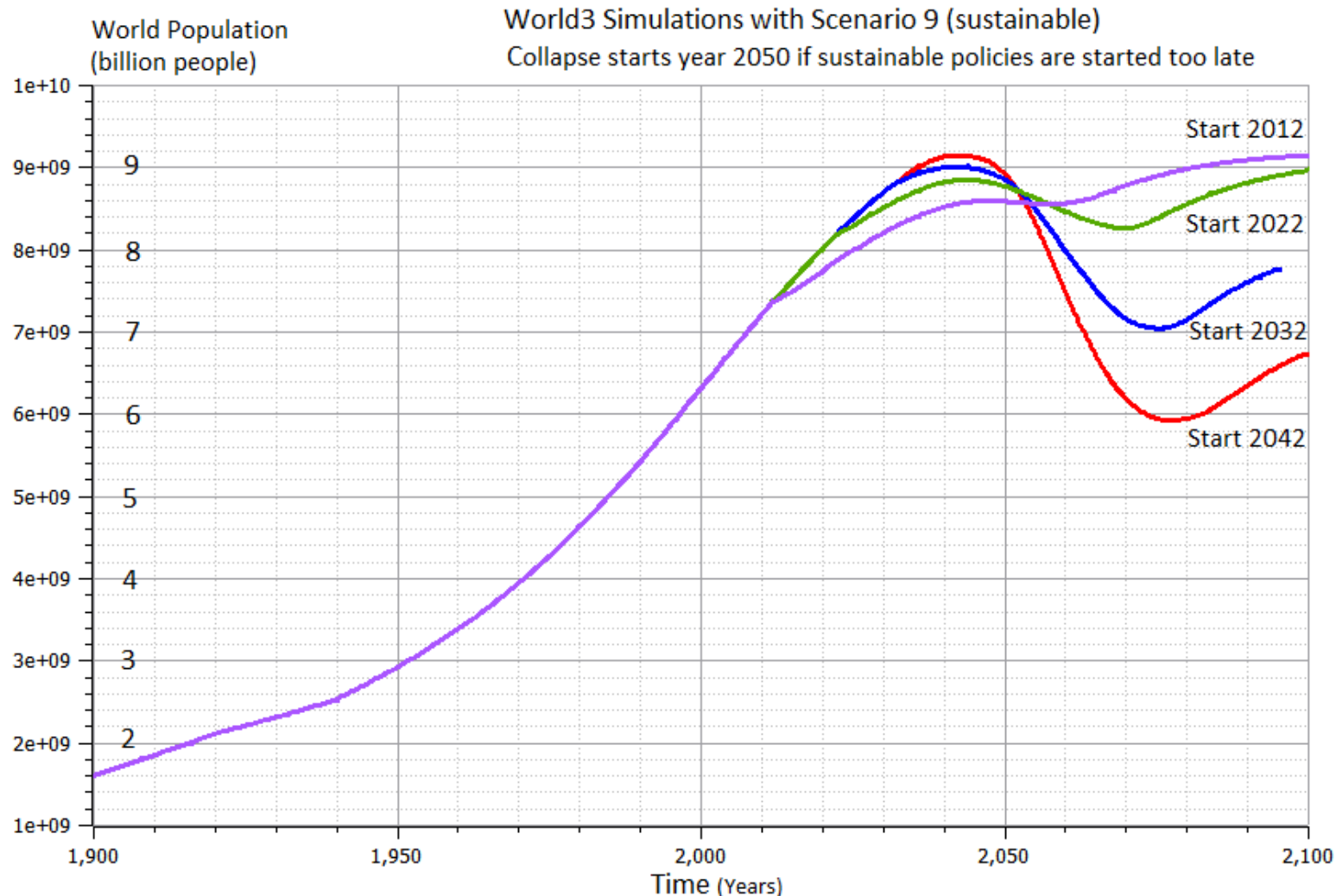
vs

Bacteria
on a
finite
substrate

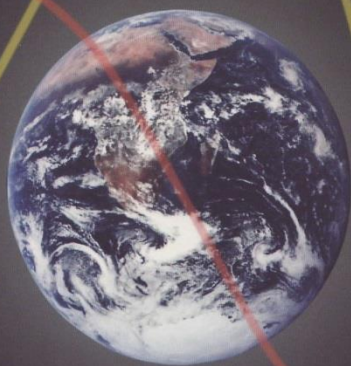


Bacterial growth curve /kinetic curve (Wikipedia)

World3 Simulations with Different Start Years for Sustainable Policies – Collapse if starting too late



LIMITS TO GROWTH



The 30-Year Update

DONELLA MEADOWS | JORGEN RANDERS | DENNIS MEADOWS

THE NEW YORK TIMES BESTSELLER

COLLAPSE

HOW SOCIETIES CHOOSE

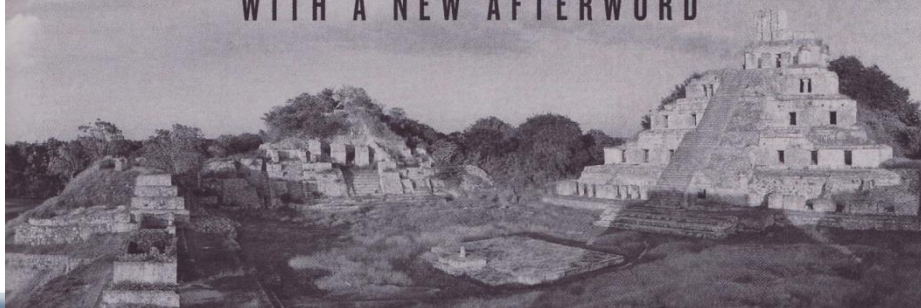
TO FAIL OR SUCCEED

JARED DIAMOND

author of the Pulitzer Prize-winning

GUNS, GERMS, and STEEL

WITH A NEW AFTERWORD

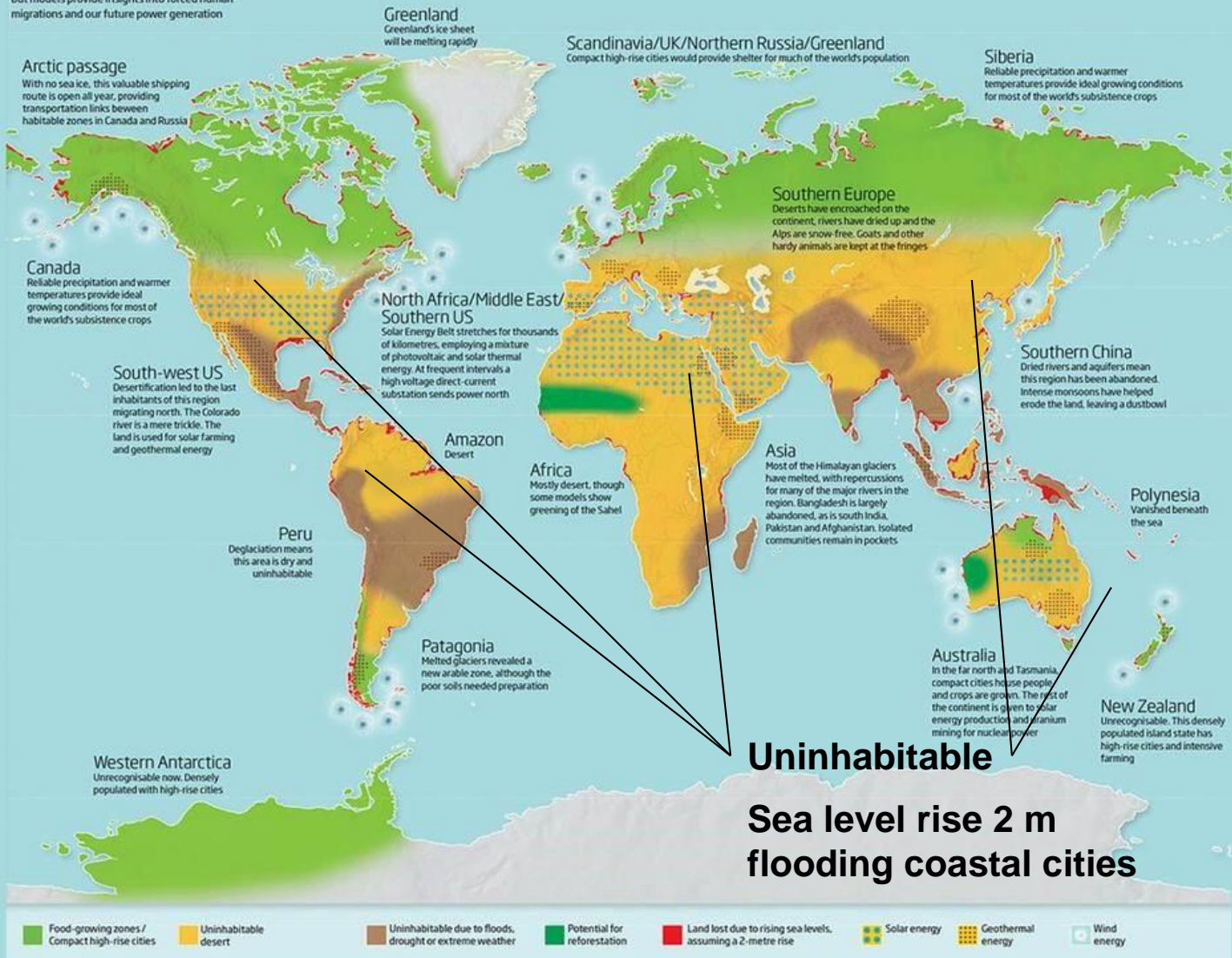


How the world could be in 80-100 years at a global warming of 4 degrees

Business-as-usual scenario, IPCC

The world: 4°C warmer

No one knows exactly what this world will look like, but models provide insights into forced human migrations and our future power generation



- Cities, agriculture
- Uninhabitable desert
- Uninhabitable due to extreme weather
- Flooded

Massive migration to northern Europe, Russia, and Canada

- Example Emissions CO2e / person
- Earth can handle 2 ton/yr
 - Flight Spain – 1 ton
 - Flight Canarys – 2 ton
 - Flight Thailand – 4 ton

References
 New Scientist, 28 february 2009
 IPCC, business as usual scenario
www.climate-lab-book.ac.uk
www.atmosfair.de

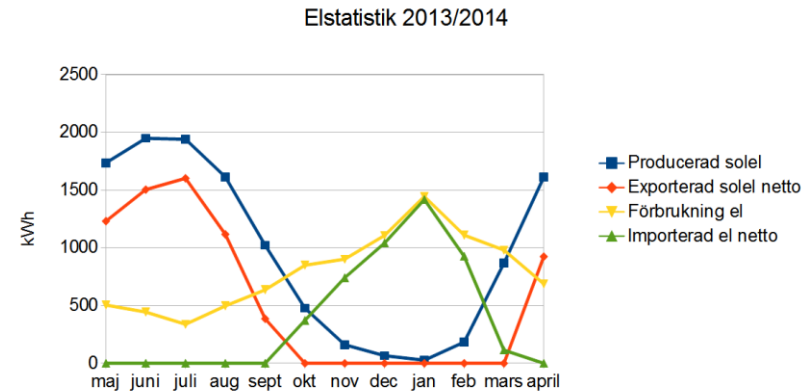
What Can You Do?

Need Global Sustainability Mass Movement

- Develop smart Cyber-Physical systems for reduced energy and material footprint
- Model-based circular economy for re-use of products and materials
- Promote sustainable lifestyle and technology
- Install electric solar PV panels
- Buy shares in cooperative wind power



20 sqm solar panels on garage roof, Nov 2012
Generated 2700 W at noon March 10, 2013



Expanded to 93 sqm, 12 kW, March 2013
House produced 11600 kWh, used 9500 kWh
Avoids 10 ton CO₂ emission per year

Example Electric Cars

Can be charged by electricity from own solar panels



Renault ZOE; 5 seat; Range:
22kwh (2014) vs 40 kwh battery (2017)

- **Realistic Swedish drive cycle:**
- **Summer: 165 km, now 300 km**
- **Winter: 110 km, now 200 km**

Cheap fast AC chargers (22kw, 43kw)



2018, Tesla Model 3 LR, range 560 km

Tesla Model S, range about 550 km



DLR ROboMObil

- **experimental electric car**
- **Modelica models**

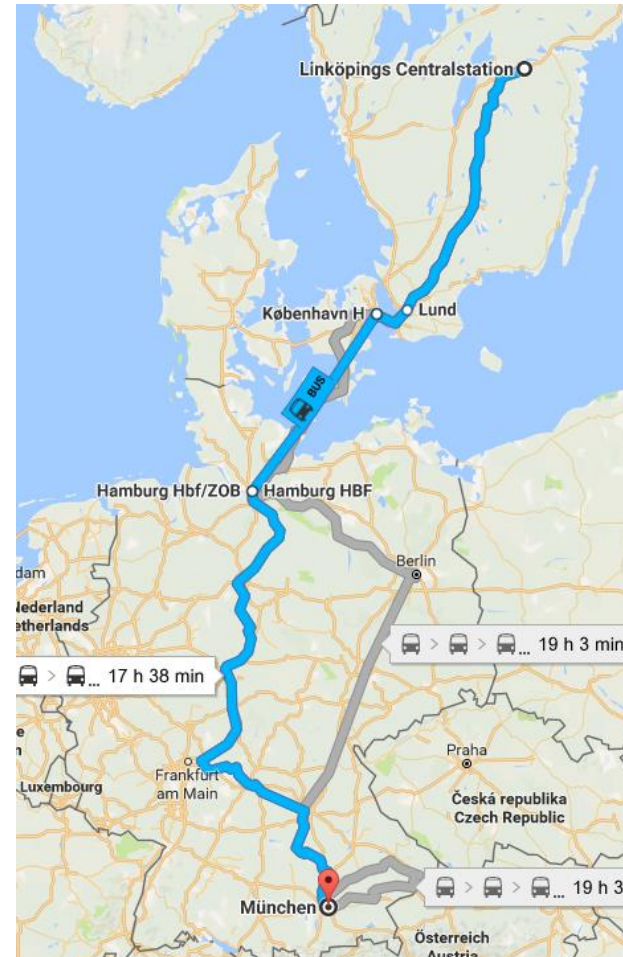
What Can You Do?

More Train Travel – Less Air Travel

- Air travel by Swedish Citizens – about the same emissions as all personal car traffic in Sweden!
- By train from Linköping to Munich and back – saves almost 1 ton of CO₂e emissions compared to flight
- Leave Linköping 07.00 in Munich 23.14

More Examples, PF travel 2016:

- Train Linköping-Paris, Dec 3-6, EU project meeting
- Train Linköping-Dresden, Dec 10-16, 1 week workshop



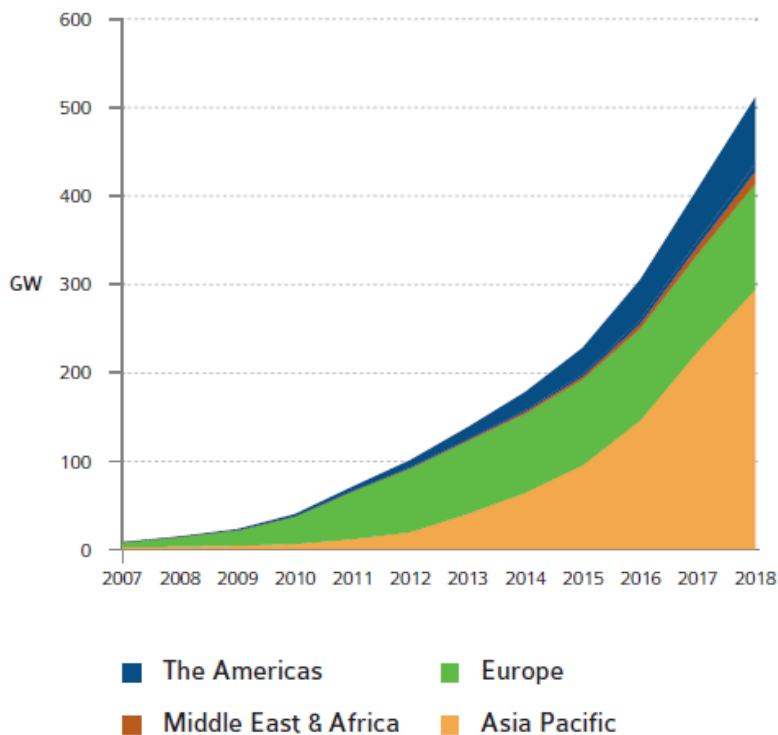
Train
travel
Linköping
- Munich

A satellite-style world map showing the Earth's continents and oceans. A yellow text box is overlaid on the map, containing the text "Small rectangles – surface needed for 100% solar energy for humanity". Several small yellow squares are placed on the map, indicating specific locations where solar energy potential is high. These squares are located in the southwestern United States, northern South America (Brazil), North Africa, the Middle East, India, Southeast Asia, and Australia. The map is set against a dark blue background representing the sky.

Small rectangles – surface needed for 100% solar energy for humanity

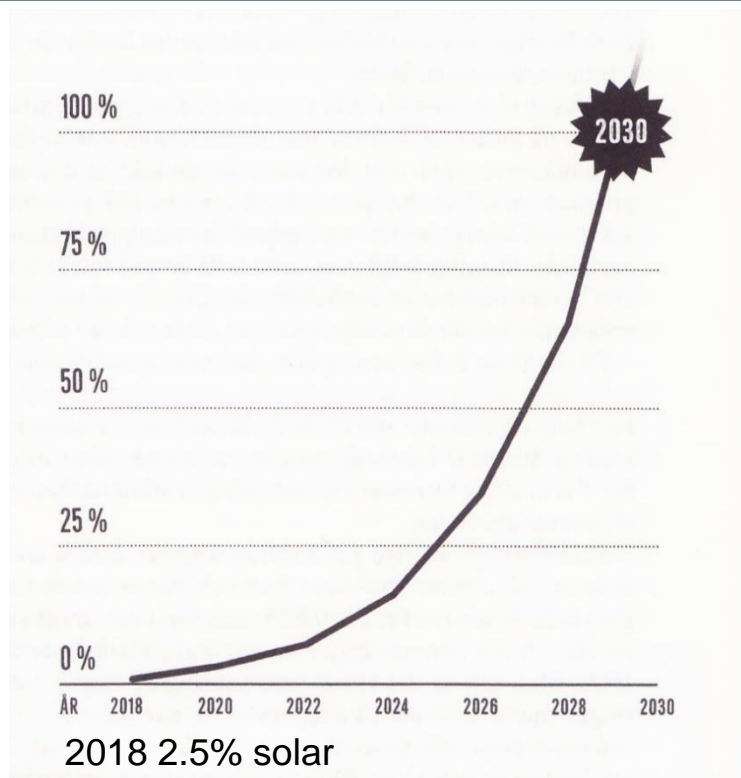
Solar Energy PhotoVoltaics Growth Trends

FIGURE 2.5: EVOLUTION OF REGIONAL PV INSTALLATIONS (GW)



Almost Exponential worldwide Growth of Photovoltaics 2006 – 2018

IEA PVPS TRENDS IN PHOTOVOLTAIC APPLICATIONS 2019



100% of global electricity production year 2030 if strong exponential growth continues

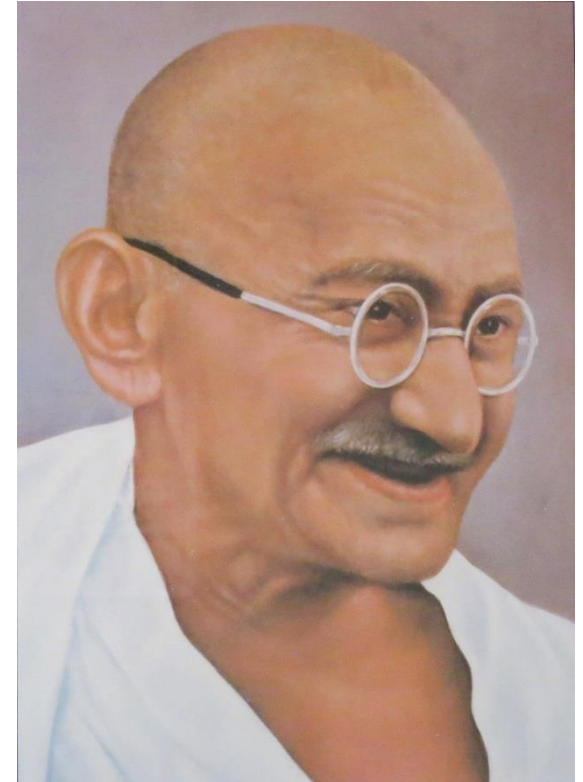
Sustainable Society Necessary for Human Survival

Almost Sustainable

- India, recently 1.4 ton CO₂/person/year
- Healthy vegetarian food
- Small-scale agriculture
- Small-scale shops
- Simpler life-style (Mahatma Gandhi)

Non-sustainable

- USA 17 ton CO₂, Sweden 7 ton CO₂/yr
- High meat consumption (1 kg beef uses ca 4000 L water for production)
- Hamburgers, unhealthy , includes beef
- Energy-consuming mechanized agriculture
- Transport dependent shopping centres
- Stressful materialistic lifestyle



Gandhi – role model for future less materialistic life style

Brief Modelica History

- First Modelica design group meeting in fall 1996
 - International group of people with expert knowledge in both language design and physical modeling
 - Industry and academia
- Modelica Versions
 - 1.0 released September 1997
 - 2.0 released March 2002
 - 2.2 released March 2005
 - 3.0 released September 2007
 - 3.1 released May 2009
 - 3.2 released March 2010
 - 3.3 released May 2012
 - 3.2 rev 2 released November 2013
 - 3.3 rev 1 released July 2014
 - 3.4 released April 2017
- Modelica Association established 2000 in Linköping
 - Open, non-profit organization

Modelica Conferences

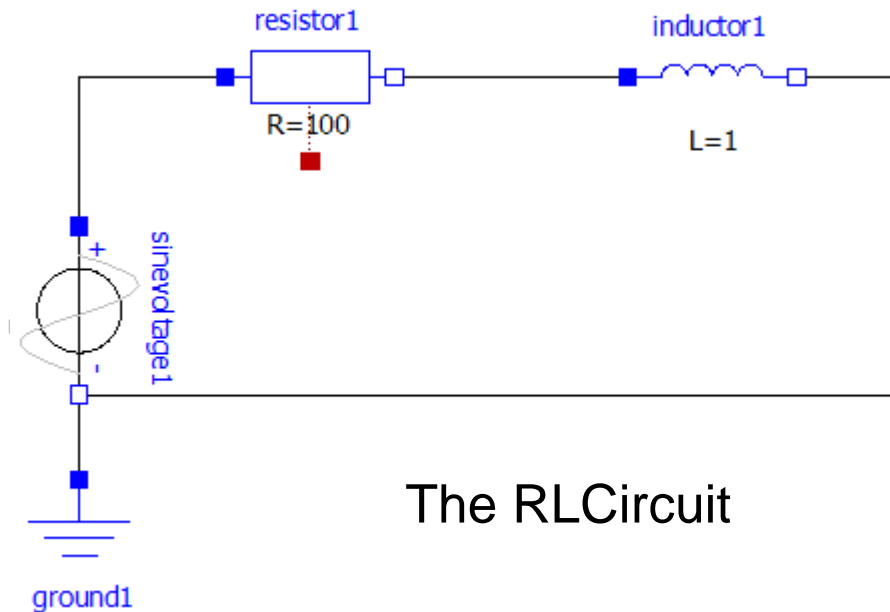
- The 1st International Modelica conference October, 2000
- The 2nd International Modelica conference March 18-19, 2002
- The 3rd International Modelica conference November 5-6, 2003 in Linköping, Sweden
- The 4th International Modelica conference March 6-7, 2005 in Hamburg, Germany
- The 5th International Modelica conference September 4-5, 2006 in Vienna, Austria
- The 6th International Modelica conference March 3-4, 2008 in Bielefeld, Germany
- The 7th International Modelica conference Sept 21-22, 2009 in Como, Italy
- The 8th International Modelica conference March 20-22, 2011 in Dresden, Germany
- The 9th International Modelica conference Sept 3-5, 2012 in Munich, Germany
- The 10th International Modelica conference March 10-12, 2014 in Lund, Sweden
- The 11th International Modelica conference Sept 21-23, 2015 in Versailles, Paris
- The 12th International Modelica conference May 15-17, 2017 in Prague, Czech Rep
- The 13th International Modelica conference March 4-6, 2019, Regensburg, Germany
- Also: Japanese Modelica conferences 2016, 2017, 2018, 2020
- Also: US Modelica conference 2018, 2020
- Coming: 14th International Modelica conference May, 2021, Linköping, Sweden

Exercises Part I

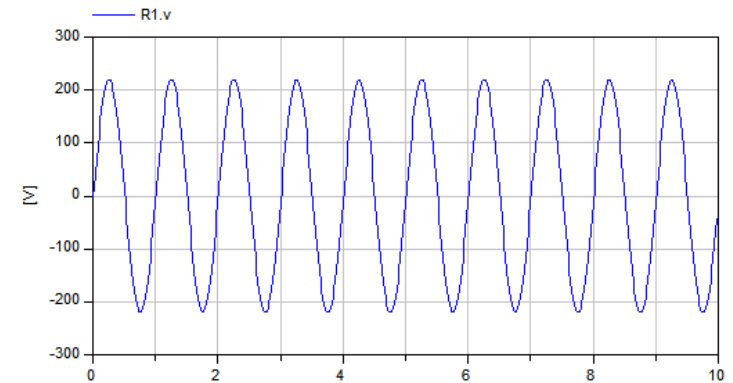
Hands-on graphical modeling (15 minutes)

Exercises Part I – Basic Graphical Modeling

- (See instructions on next two pages)
- Start the OMEdit editor (part of OpenModelica)
- Draw the RLCircuit
- Simulate



The RLCircuit



Simulation


Exercises Part I – OMEdit Instructions (Part I)

- Start OMEdit from the Program menu under OpenModelica
- Go to **File** menu and choose **New Modelica Class**, and then select **Model**.
- E.g. write *RLCircuit* as the model name.
- For more information on how to use OMEdit, go to **Help** and choose **User Manual** or press **F1**.

Under the **Modelica Library**:

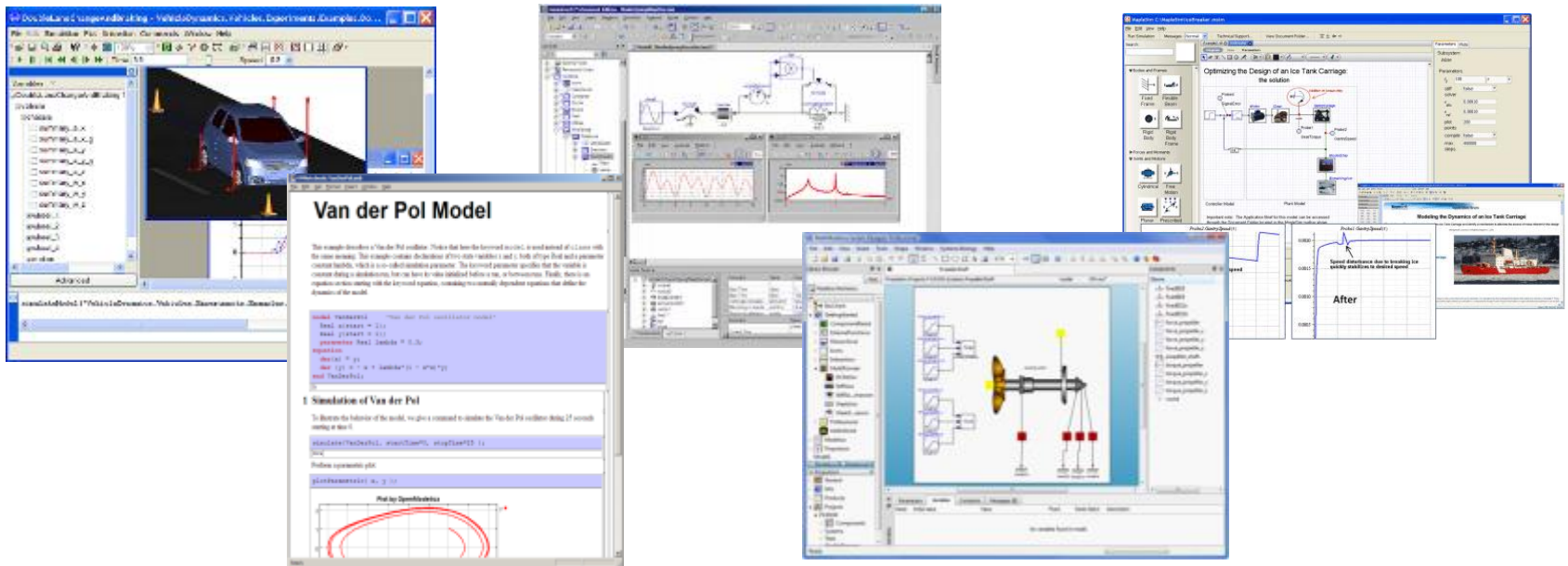
- Contains The standard Modelica library components
- The **Modelica files** contains the list of models you have created.

Exercises Part I – OMEdit Instructions (Part II)

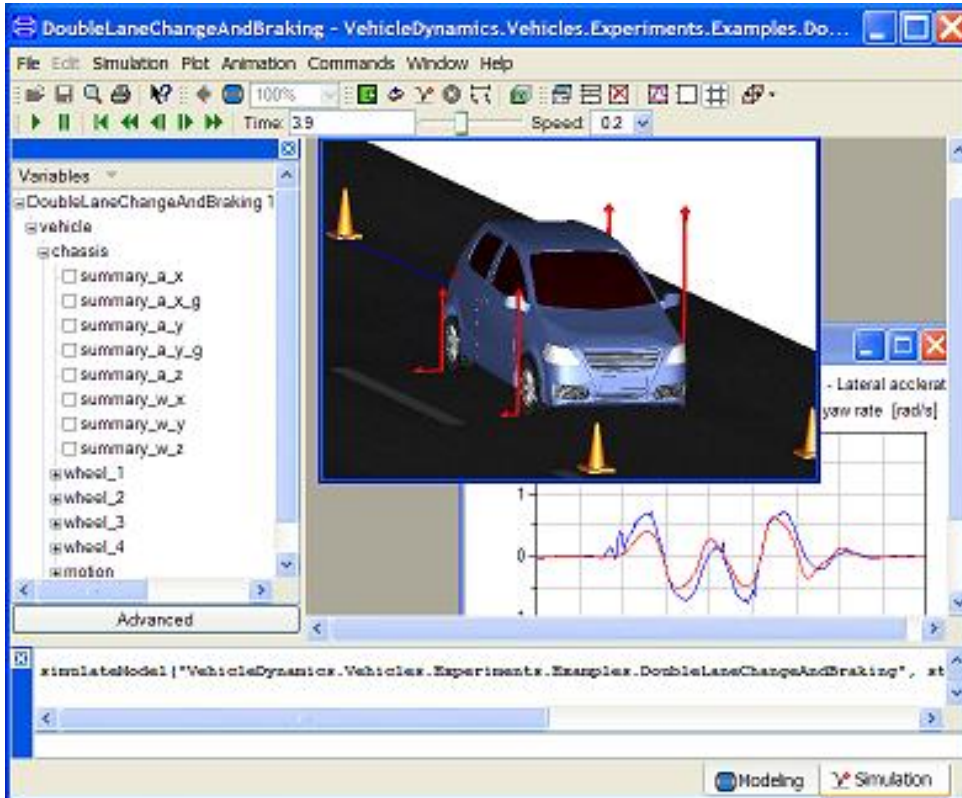
- For the RLCircuit model, **browse** the Modelica standard library and **add** the following component models:
 - Add `Ground`, `Inductor` and `Resistor` component models from `Modelica.Electrical.Analog.Basic` package.
 - Add `SineVoltage` component model from `Modelica.Electrical.Analog.Sources` package.
- Make the corresponding **connections** between the component models as shown in the previous slide.
- To **draw a connection line**: first single-click on a connector box; then start drawing while keeping the mouse button down; after drawing a little you can release the mouse button and continue drawing.
- **Simulate** the model
 - Go to the Simulation menu and choose simulate or click on the simulate button  in the toolbar.
- **Plot** the instance variables
 - Once the simulation is completed, a plot variables list will appear on the right side. Select the variable that you want to plot.

Part II

Modelica environments and OpenModelica

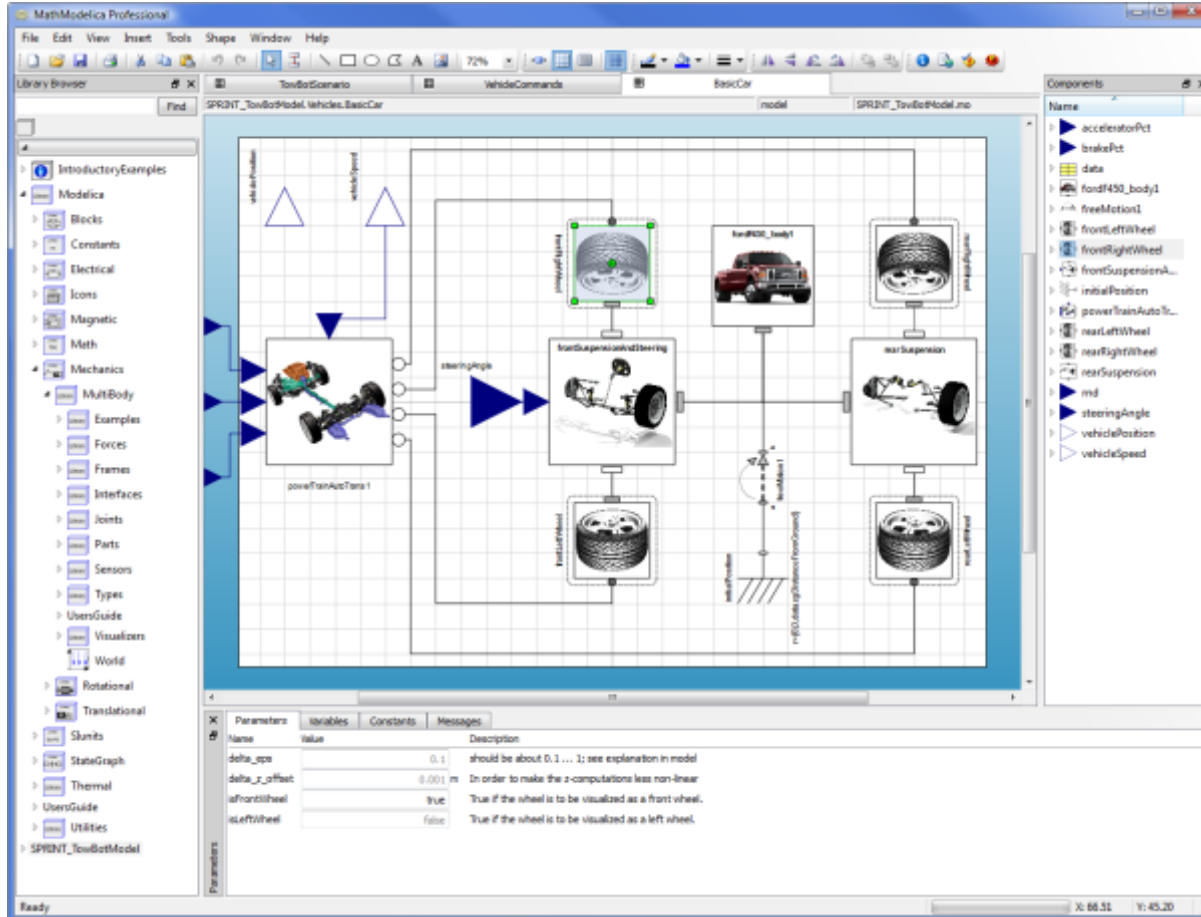


Dymola

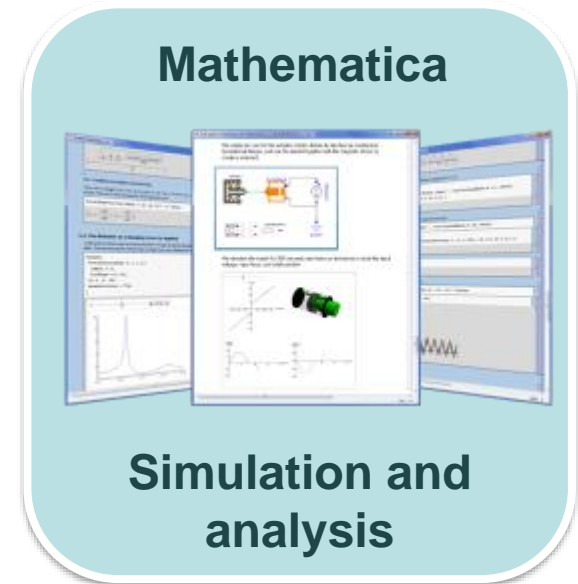


- Dassault Systemes Sweden
- Sweden
- First Modelica tool on the market
- Initial main focus on automotive industry
- www.dymola.com

Wolfram System Modeler – Wolfram MathCore



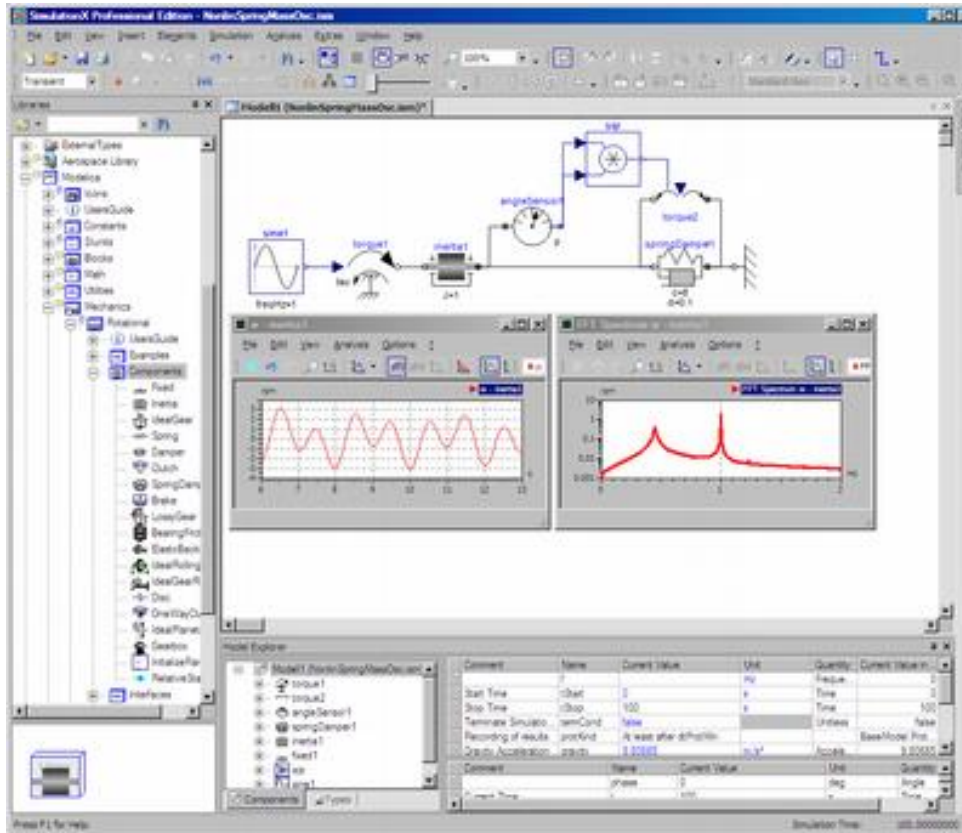
- Wolfram Research
- USA, Sweden
- General purpose
- Mathematica integration
- www.wolfram.com
- www.mathcore.com



Car model graphical view

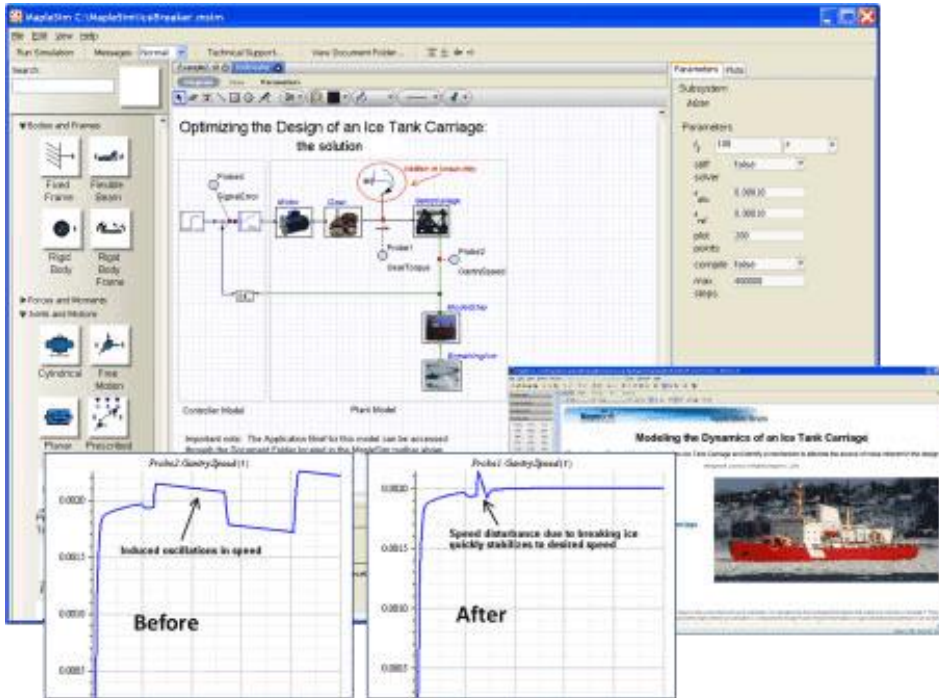
Courtesy
Wolfram
Research

Simulation X



- ITI GmbH (Part of ESI Group)
- Germany
- Mechatronic systems
- www.simulationx.com

MapleSim



- Maplesoft
- Canada
- Integrated with Maple
- www.maplesoft.com

Modelon



Modelon Library Suite

Powered by Modelica

Our suite of libraries, built on the Modelica open standard, delivers state-of-the-art system models for a wide range of industrial applications.



Modelon Creator Suite

Our creator suite is a powerful platform for model creation, automation, simulation and optimization.



Modelon Deployment Suite

Powered by FMI

Our comprehensive suite of deployment products, built on the FMI open standard, enables collaboration and rapid deployment of system models across multiple platforms, varying tools, and organizations.

- Modelon
- Sweden and International
- Library Suite
- Creator Suite with Optimica Compiler Toolbox and WAMS model editor
- www.modelon.com

The OpenModelica Environment

www.OpenModelica.org

The screenshot shows the OpenModelica website homepage. At the top, the logo "OpenModelica" is displayed in blue and black text against a background of water droplets. To the right of the logo are links for "Login" and "Create an account". Below the logo is a navigation menu with tabs for "HOME", "DOWNLOAD", "TOOLS & APPS", "USERS", "DEVELOPERS", "FORUM", "EVENTS", and "RESEARCH". A search bar is located on the right side of the menu.

The main content area is divided into several sections:

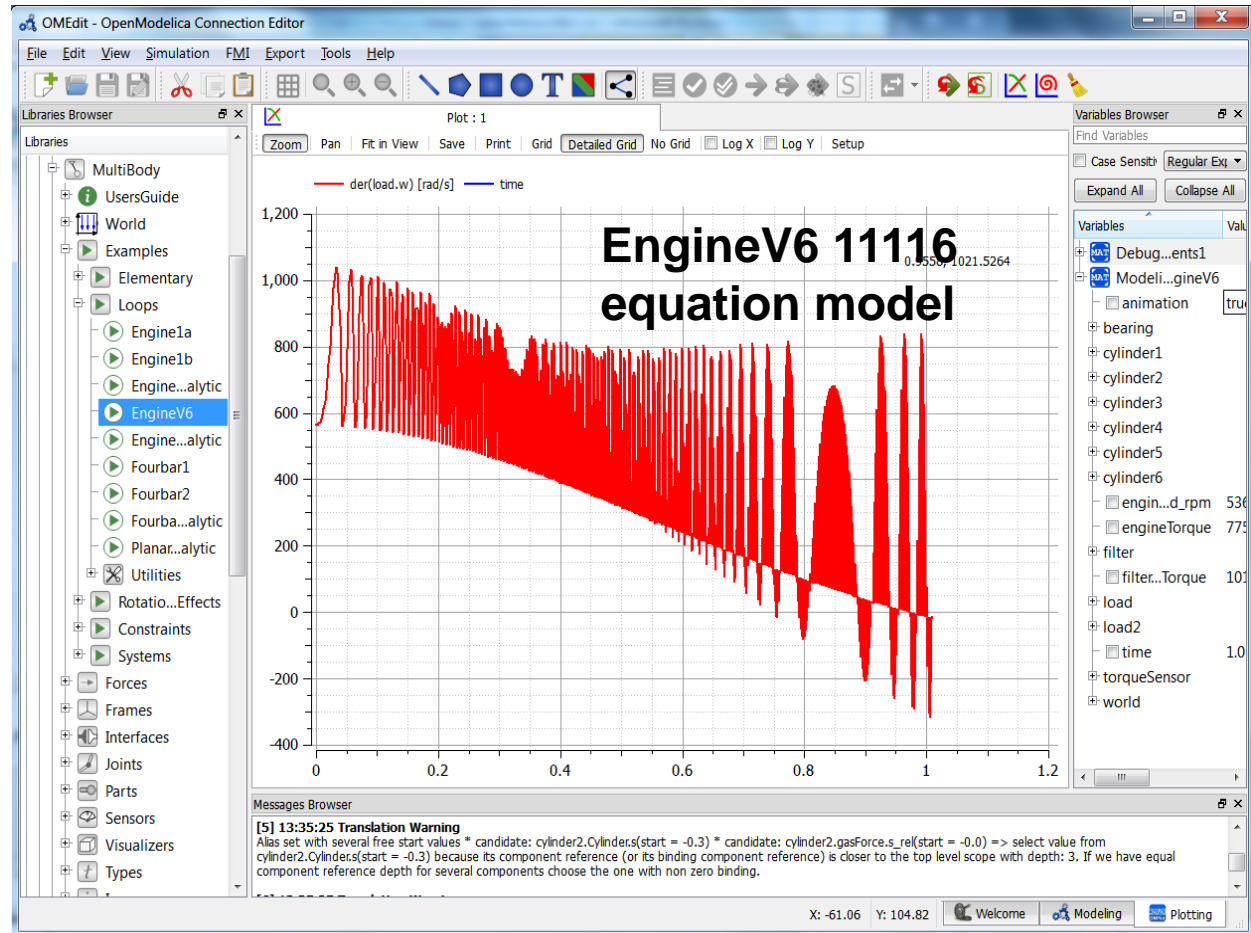
- Top information:** A sidebar on the left containing three items:
 - Industrial Products:** Commercial Applications using OpenModelica, accompanied by a small image of a factory.
 - OMEdit:** Enhanced OpenModelica Connection Editor, accompanied by a gear icon.
 - Library Coverage:** Latest library coverage, accompanied by a small image of a library.
- Introduction:** A central text block stating: "OPENMODELICA is an open-source Modelica-based modeling and simulation environment intended for industrial and academic usage. Its long-term development is supported by a non-profit organization – the Open Source Modelica Consortium (OSMC). The goal with the OpenModelica effort is to create a comprehensive Open Source Modelica modeling, compilation and simulation environment based on free software distributed in binary and source code form for research, teaching, and industrial usage. We invite researchers and students, or any interested developer to participate in the project and cooperate around OpenModelica, tools, and applications." Below this text is a screenshot of the OMEdit software interface showing various windows and a plot.
- Latest news:** A sidebar on the right listing recent releases and events:
 - October 25, 2014: OpenModelica 1.9.1 released
 - Preliminary Program OpenModelica Annual Workshop 2015
 - October 07, 2014: OpenModelica 1.9.1 Beta4 released
 - March 08, 2014: OpenModelica 1.9.1 Beta2 released
 - New Book: Peter Fritzson - Principles of Object-Oriented Modeling and Simulation with Modelica 3.3
 - February 02, 2014: OpenModelica 1.9.1 Beta1 released
 - CFP OpenModelica Workshop February 2014
 - October 09, 2013: OpenModelica 1.9.0 released
 - September 27, 2013: OpenModelica 1.9.0 RC1 released
 - February 1, 2013: OpenModelica 1.9.0 Beta4 released
- Modelica/OpenModelica Videos:** A section at the bottom left featuring a video player with the title "Overview of Modelica, an Open Source Modelica Consortium".

At the bottom of the main content area, there are several links and instructions:

- Register yourself** to get information about new releases.
- Participate in the **OpenModelicaInterest mailing list**.
- Help us: get the latest **source code** or **nightly-build** and report bugs.
- To learn about Modelica, read a **book** or a **tutorial** about Modelica®.
- For systems engineering with requirement traceability and verification, see **ModelicaML**.

OpenModelica – Free Open Source Tool developed by the Open Source Modelica Consortium (OSMC)

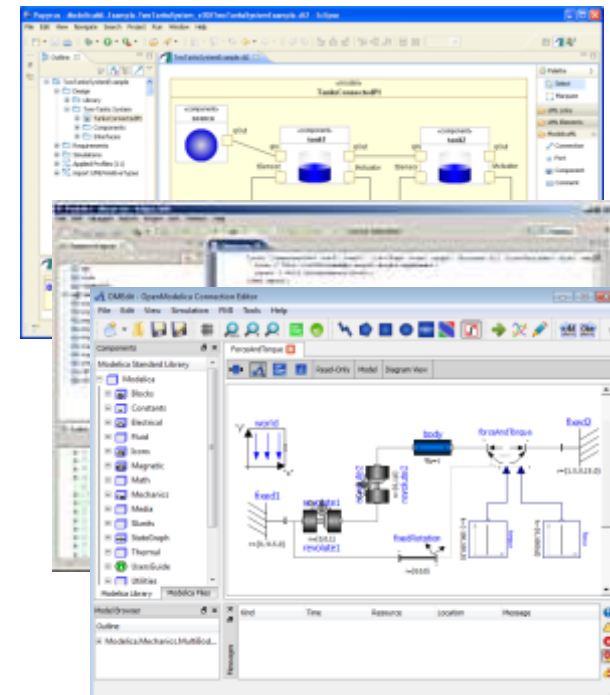
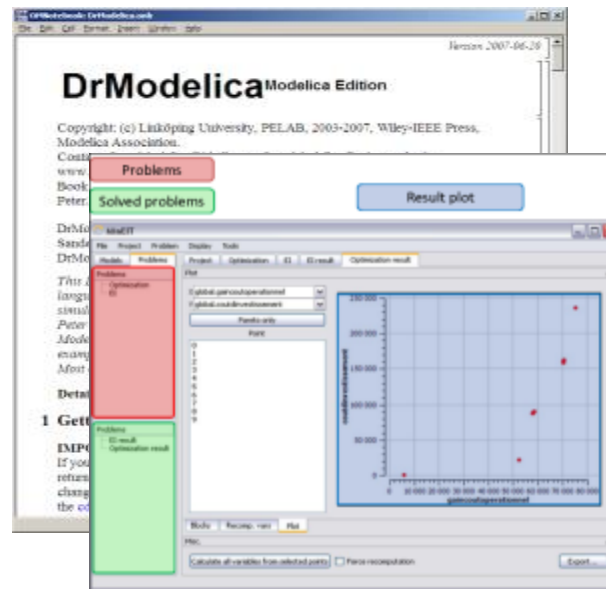
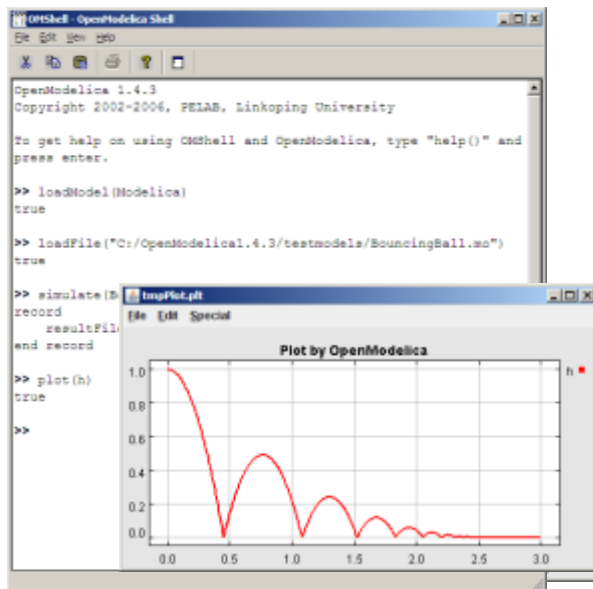
- Graphical editor
- Model compiler and simulator
- Debugger
- Performance analyzer
- Dynamic optimizer
- Symbolic modeling
- Parallelization
- Electronic Notebook and OMWebbook for teaching
- Spokentutorial for teaching



The OpenModelica Open Source Environment

www.openmodelica.org

- Advanced Interactive Modelica compiler (OMC)
 - Supports most of the Modelica Language
 - **Modelica, Python, Julia scripting**
- OMSimulator – FMI Simulation/Co-simulation
- Basic environment for creating models
 - **OMShell** – an interactive command handler
 - **OMNotebook** – a literate programming notebook
 - **MDT** – an advanced textual environment in Eclipse
- **OMEdit** graphic Editor
- **OMDebugger** for equations
- **OMOptim** optimization tool
- **OM Dynamic optimizer** collocation
- **ModelicaML** UML Profile
- **MetaModelica** extension
- **ParModelica** extension



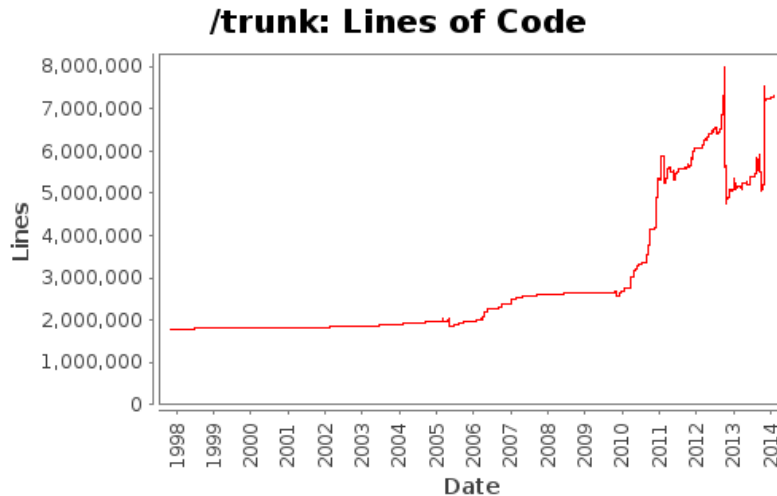
OSMC – International Consortium for Open Source Model-based Development Tools, 51 members Dec 2019

Founded Dec 4, 2007

Open-source community services

- Website and Support Forum
- Version-controlled source base
- Bug database
- Development courses
- www.openmodelica.org

Code Statistics



Industrial members

- ABB AB, Sweden
- Bosch Rexroth AG, Germany
- CDAC Centre, Kerala, India
- Creative Connections, Prague
- DHI, Aarhus, Denmark
- Dynamica s.r.l., Cremona, Italy
- EDF, Paris, France
- Equa Simulation AB, Sweden
- Fraunhofer IWES, Bremerhaven
- INRIA, Rennes, France
- ISID Dentsu, Tokyo, Japan
- Maplesoft, Canada
- RTE France, Paris, France
- Saab AB, Linköping, Sweden
- SKF, Göteborg, Sweden
- SmartFluidPower, Italy
- TLK Thermo, Germany
- Siemens Turbo, Sweden
- Sozhou Tongyuan, China
- SRON Space Ins Netherlands
- Talent Swarm, Spain
- VTI, Linköping, Sweden
- VTT, Finland

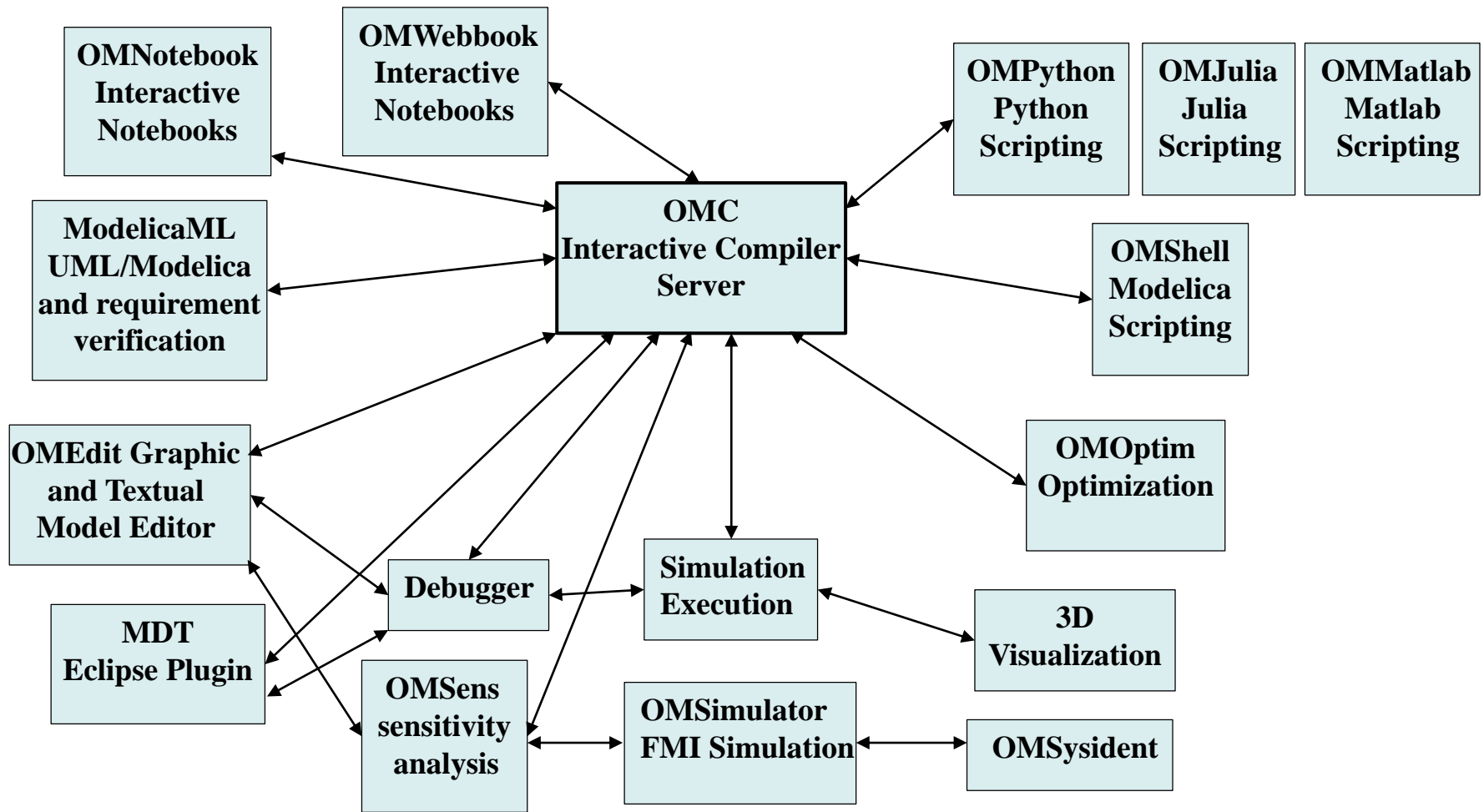
University members

- Augsburg University, Germany
- FH Bielefeld, Bielefeld, Germany
- University of Bolivar, Colombia
- TU Braunschweig, Germany
- Chalmers Univ, Control, Sweden
- Chalmers Univ, Machine, Sweden
- TU Darmstadt, Germany
- TU Delft, The Netherlands
- TU Dresden, Germany
- Université Laval, Canada
- Georgia Inst of Technology, USA
- Ghent University, Belgium
- Halmstad University, Sweden
- Heidelberg University, Germany
- TU Hamburg/Harburg Germany
- IIT Bombay, Mumbai, India
- K.L. Univ, Waddeswaram, India
- KTH, Stockholm, Sweden
- Linköping University, Sweden
- Univ of Maryland, Syst Eng USA
- Univ of Maryland, CEEE, USA
- Politecnico di Milano, Italy
- Ecoles des Mines, CEP, France
- Mälardalen University, Sweden
- RPI, Troy, USA
- Univ Pisa, Italy
- Univ College SouthEast Norway
- Tsinghua Univ, Beijing, China
- Vanderbilt Univ, USA

Build System with Regression Testing

- Automatic Nightly build system (using Jenkins), and several multi-core computers
- Regression testing of libraries
- Verification testing comparing results to references

The OpenModelica Tool Architecture



Spoken-Tutorial step-by-step OpenModelica and Modelica Tutorial Using OMEdit. Link from www.openmodelica.org

OpenModelica Login Create an account

Spoken Tutorial Software Training Creation News Forums About Statistics

HOME DOWNLOAD TOOLS & APPS

Search Tutorials

https://spoken-tutorial.org/tutorial-search/?search_foss=OpenModelica&search_language=English

To learn about Modelica, read a [book](#) or a [tutorial](#) about Modelica®.
 Interactive step-by-step beginners Modelica on-line spoken tutorials
 Interactive [OMWebbook](#) with examples of Modelica textual modeling

04)

OpenModelica is an open source modelling and simulation environment intended for industrial and academic usage. It is an object oriented declarative multi domain modelling language for complex systems. This environment can be used to work for both steady state as well as dynamic systems. Attractive strategy when dealing with design and optimization problems. As all the equations are solved simultaneously it doesn't matter whether the unknown variable in an input or output variable. [Read more](#)

About 12 results found.

[Instruction Sheet](#)



1. Introduction to OMEdit

Foss : OpenModelica - English

Outline: Introduction to OpenModelica Introduction to OMEdit Perspectives in OMEdit Browsers in OMEdit View icons in OMEdit Open a Class from Libraries Browser Checking for correctness..

Basic

Progress bar



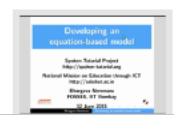
2. Examples through OMEdit

Foss : OpenModelica - English

Outline: Expand Modelica library Expand Electrical library Expand Analog library Open Rectifier Class Compare the values of IDC & Losses time vs Losses plot Expand Mechanics library ..

Basic

Progress bar



3. Developing an equation-based model

Foss : OpenModelica - English

Outline: Introduction to OMEdit Declaration of variables and equations Simulation of a model in

Basic

Progress bar



OMNotebook Electronic Notebook with DrModelica

- Primarily for teaching
- Interactive electronic book
- Platform independent

Commands:

- *Shift-return (evaluates a cell)*
- File Menu (open, close, etc.)
- Text Cursor (vertical), Cell cursor (horizontal)
- Cell types: text cells & executable code cells
- Copy, paste, group cells
- Copy, paste, group text
- Command Completion (shift-tab)



The screenshot shows a window titled "OMNotebook: DrModelica.omb*" with a menu bar (File, Edit, Cell, Format, Insert, Window, Help) and a status bar (Ready). The main content area displays the following text:

Version 2006-04-11

DrModelica Modelica Edition

Copyright: (c) Linköping University, PELAB, 2003-2006, Wiley-IEEE Press, Modelica Association.
Contact: OpenModelica@ida.liu.se; [OpenModelica Project web site](http://OpenModelica.org)
www.ida.liu.se/projects/OpenModelica
Book web page: www.mathcore.com/drModelica; Book author: Peter.Fritzson@ida.liu.se

DrModelica Authors: (2003 version) Susanna Monemar, Eva-Lena Lengquist-Sandelin, Peter Fritzson, Peter Bounie
DrModelica Authors: (2005 and later updates): Peter Fritzson

This DrModelica notebook has been developed to facilitate learning the Modelica language as well as providing an introduction to object-oriented modeling and simulation. It is based on and is supplementary material to the Modelica book: Peter Fritzson: "Principles of Object-Oriented Modeling and Simulation with Modelica" (2004), 940 pages, Wiley-IEEE Press, ISBN 0-471-47163-1. All of the examples and exercises in DrModelica and the page references are from that book. Most of the text in DrModelica is also based on that book.

Detailed Copyright and Acknowledgment Information

Getting Started Using OMNotebook

OpenModelica commands

Berkeley license OpenModelica

1 A Quick Tour of Modelica

1.1 Getting Started - First Basic Examples

There is a long tradition that the first sample program in any computer language is a trivial program printing the string "Hello World" (p. 19 in Peter Fritzson's book). Since Modelica is an equation based language, printing a string does not make much sense. Instead, our Hello World Modelica program solves a trivial differential equation. The second example shows how you can write a model that solves a [Differential Algebraic Equation System](#) (p. 19). In the [Van der Pol](#) (p. 22) example declaration as well as initialization and prefix usage are shown in a slightly more complicated way.

1.2 Classes and Instances

In Modelica objects are created implicitly just by [Declaring Instances of Classes](#) (p. 26). Almost anything in Modelica is a class, but there are some keywords for specific use of the class concept, called

OMnotebook Interactive Electronic Notebook Here Used for Teaching Control Theory

1 Kalman Filter

Often we don't have access to the internal states of a system. We have to reconstruct the state of the system based on measurements. The idea with an observer is that we feedback the error. If the estimation is correct then the difference should be zero.

Another difficulty is that the measured quantities of

$$\begin{cases} \dot{\hat{x}} = \\ y \end{cases}$$

Here e denoting a disturbance in the input signal is to be evaluated by the difference

$$K(y(t) - \hat{y}(t))$$

By using this quantity as feedback we obtain the observer

$$\dot{\hat{x}} = A\hat{x}(t) + Bu(t) + K(y(t) - \hat{y}(t))$$

Now form the error as

The differential error is

The screenshot shows the OMNotebook interface with a model definition for a Kalman filter. The model is named 'KalmanFeedback' and contains several parameters and state space definitions. The parameters are:

- Real A[:, size(A, 1)] = {{0,1},{1,0}};
- Real B[size(A, 1),:] = {{0},{1}};
- Real C[:, size(A, 1)] = {{1,0}};
- Real[2,1] K = [2.4;3.4];
- Real[1,2] L = [2.4,3.4];
- Real[:, :] ABL = A-B*L;
- Real[:, :] BL = B*L;
- Real[:, :] Z = zeros(size(ABL, 2), size(AKC, 1));
- Real[:, :] AKC = A-K*C;
- Real[:, :] Anew = [0,1,0,0 ; -1.4, -3.4, 2.4,3.4; 0,0,-2.4,1;0,0,-2.4,0];
- Real[:, :] Bnew = [0;1;0;0];
- Real[:, :] Fnew = [1;0;0;0];

The state space noise is defined as:

```
stateSpaceNoise Kalman(stateSpace.A=Anew,stateSpace.B=Bnew, stateSpace.C=[1,0,0,0],
stateSpace.F = Fnew);
stateSpaceNoise noKalman;
```

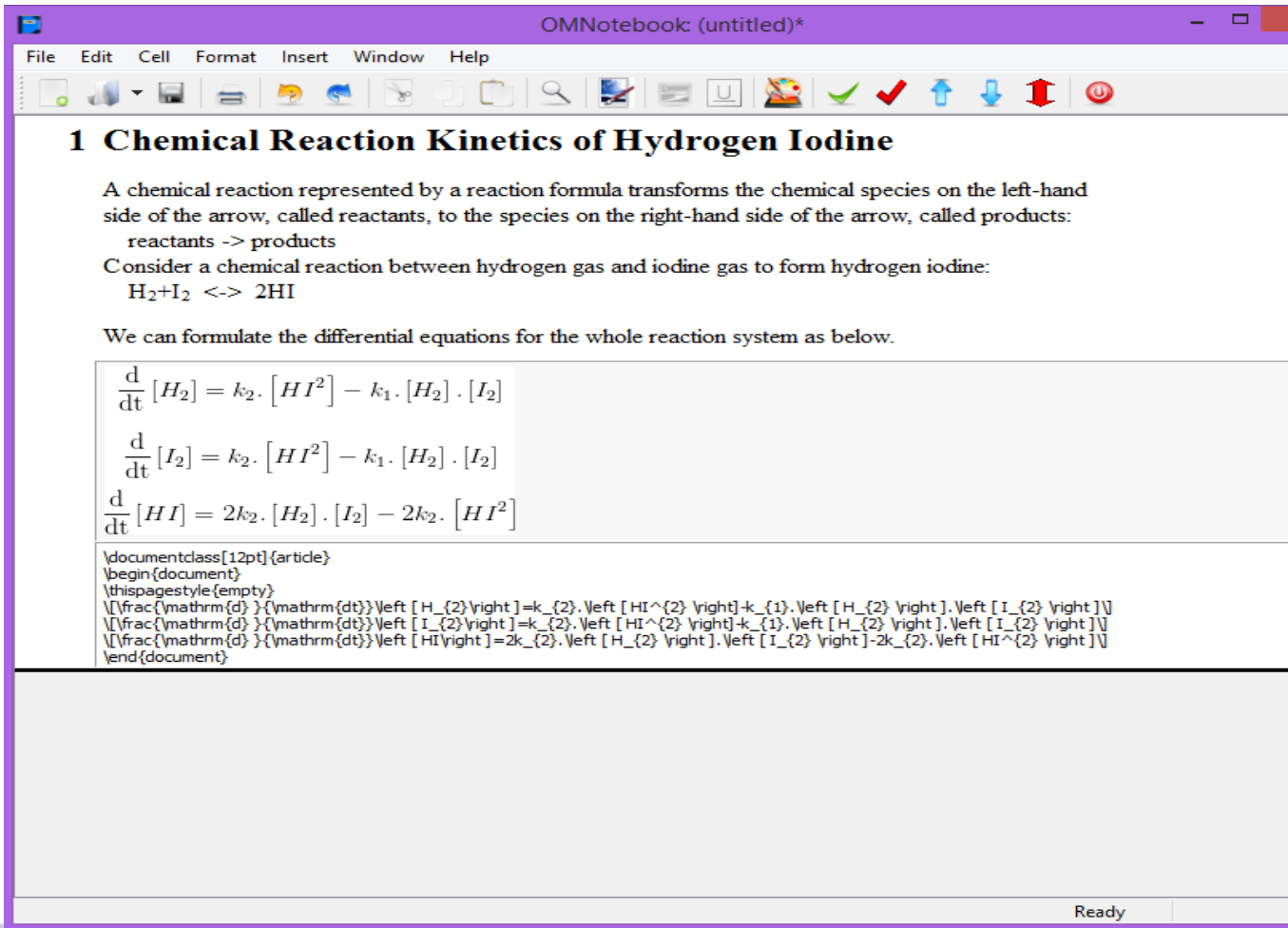
The simulation and plotting commands are:

```
simulate(KalmanFeedback,stopTime=3)
plot({Kalman.stateSpace.y[1],noKalman.stateSpace.y[1]})
```

The plot, titled 'Plot by OpenModelica', shows two time series. The x-axis represents time from 0 to 3, and the y-axis represents the state value from 0 to 15. The red line represents 'Kalman.stateSpace.y[1]' and the blue line represents 'noKalman.stateSpace.y[1]'. Both lines show a similar upward trend, but the blue line exhibits significantly more noise than the red line, which is smoother.

Mathematical Typesetting in OMNotebook and OMWebbook

OMNotebook supports Latex formatting for mathematics



OMNotebook: (untitled)*

File Edit Cell Format Insert Window Help

1 Chemical Reaction Kinetics of Hydrogen Iodine

A chemical reaction represented by a reaction formula transforms the chemical species on the left-hand side of the arrow, called reactants, to the species on the right-hand side of the arrow, called products:
reactants \rightarrow products

Consider a chemical reaction between hydrogen gas and iodine gas to form hydrogen iodine:
 $H_2 + I_2 \leftrightarrow 2HI$

We can formulate the differential equations for the whole reaction system as below.

$$\frac{d}{dt} [H_2] = k_2 \cdot [HI]^2 - k_1 \cdot [H_2] \cdot [I_2]$$
$$\frac{d}{dt} [I_2] = k_2 \cdot [HI]^2 - k_1 \cdot [H_2] \cdot [I_2]$$
$$\frac{d}{dt} [HI] = 2k_2 \cdot [H_2] \cdot [I_2] - 2k_1 \cdot [HI]^2$$

```
\documentclass[12pt]{article}
\begin{document}
\thispagestyle{empty}
\[\frac{\mathrm{d}}{\mathrm{dt}}\mathrm{[H_2]}=k_2\cdot\mathrm{[HI]^2}-k_1\cdot\mathrm{[H_2]}\cdot\mathrm{[I_2]}\]
\[\frac{\mathrm{d}}{\mathrm{dt}}\mathrm{[I_2]}=k_2\cdot\mathrm{[HI]^2}-k_1\cdot\mathrm{[H_2]}\cdot\mathrm{[I_2]}\]
\[\frac{\mathrm{d}}{\mathrm{dt}}\mathrm{[HI]}=2k_2\cdot\mathrm{[H_2]}\cdot\mathrm{[I_2]}-2k_1\cdot\mathrm{[HI]^2}\]
\end{document}
```

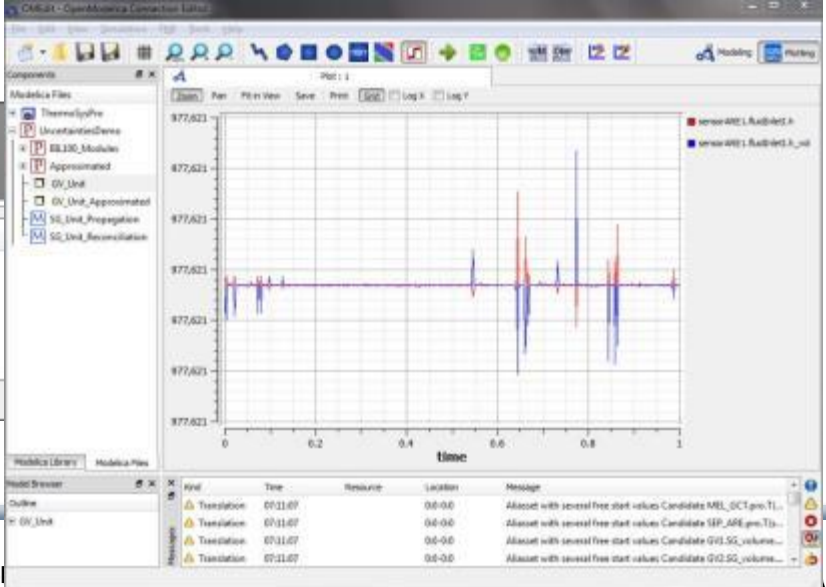
Ready

Contents in
OMWebbook
Generated from
OMNotebook

Latex instructions
can be hidden by
double clicking the
Cell in tree view

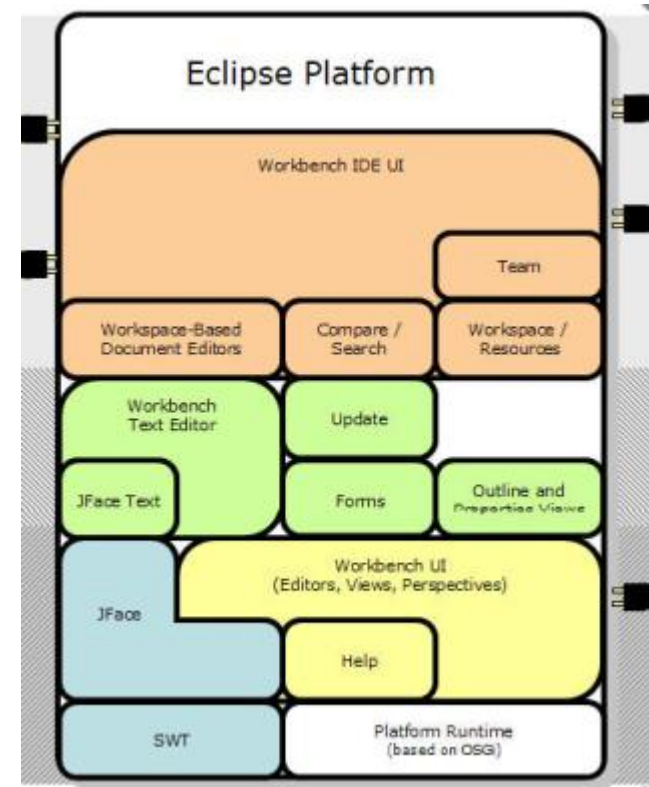
OpenModelica Environment Demo

The screenshot displays the OpenModelica Connection Editor (OMEdit) interface. The main workspace shows a detailed process flow diagram for a unit named 'GV_Unit'. The diagram consists of several interconnected components, including pumps, tanks, and a 'QPURG' block, all connected by pipes and control lines. The interface includes a menu bar (File, Edit, View, Simulation, FMI, Tools, Help), a toolbar with various icons, and a components list on the left side. The model browser at the bottom shows the 'GV_Unit' component selected.



OpenModelica MDT – Eclipse Plugin

- Browsing of packages, classes, functions
- Automatic building of executables; separate compilation
- Syntax highlighting
- Code completion, Code query support for developers
- Automatic Indentation
- Debugger
(Prel. version for algorithmic subset)



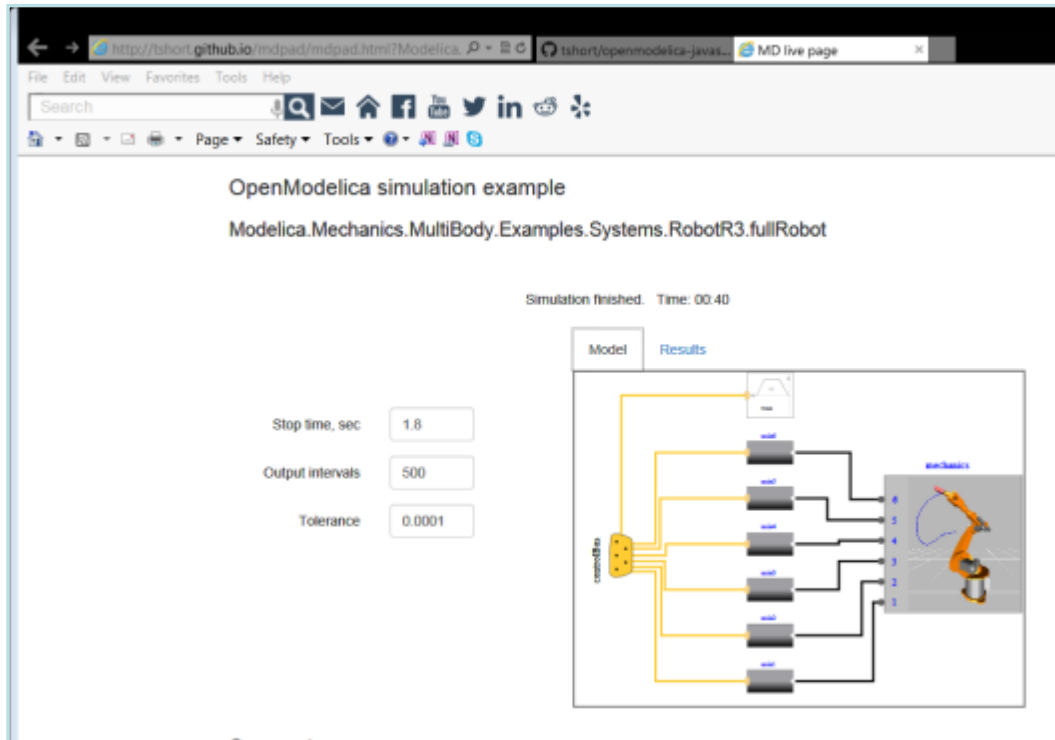
OpenModelica MDT: Code Outline and Hovering Info

The screenshot displays the Eclipse IDE interface for OpenModelica. The top-left pane shows a project tree with files like `rml2sig`, `runtime`, `scripts`, `test_codegen`, `tools`, `VC7`, and `Absyn.mo`. The bottom-left pane shows a code outline for `Absyn` with entries such as `ADD`, `ALG_ASSIGN`, `ALG_BREAK`, `ALG_CATCH`, `ALG_EQUALITY`, `ALG_FAILURE`, `ALG_FOR`, `ALG_GOTO`, `ALG_IF`, `ALG_LABEL`, `ALG_NORET_CALL`, `ALG_RETURN`, `ALG_THROW`, `ALG_TRY`, and `ALG_WHEN_A`. The main editor shows the `Absyn.mo` file with code including `case (MATRIX(matrix = exp11))`, `local list<list<list<ComponentRef>>> res1;`, `equation`, `res1 = Util.listListMap(exp11, getCrefFromExp);`, `res2 = Util.listFlatten(res1);`, `res = Util.listFlatten(res2);`, `then`, `res;`, `case (RANGE(start = e1, step = SOME(e3), stop = e2))`, `equation`, `l1 = getCrefFromExp(e1);`, `l2 =`, `res1`, `l3 =`, `res =`, `input Exp inExp;`, `then`, `res;`, `output list<ComponentRef> outComponentRefList;`, `algorithm`, `outComponentRefList:=matchcontinue inExp`, `equation`, `local`, `l1 =`, `ComponentRef cr;`, `l2 =`, `res = listAppend(l1, l2);`, `then`. A tooltip is visible over the `getCrefFromExp` function call, displaying its signature and description: `function getCrefFromExp "function: getCrefFromExp"`, `Returns a flattened list of the`, `component references in an expression"`, `input Exp inExp;`, `output list<ComponentRef> outComponentRefList;`. The bottom-right pane shows a `Problems` view with 113 errors, 0 warnings, and 0 infos. The error description is `The identifier at start and end are different`. The bottom status bar shows `64M of 254M` and `Ctrl Contrib (Bottom)`.

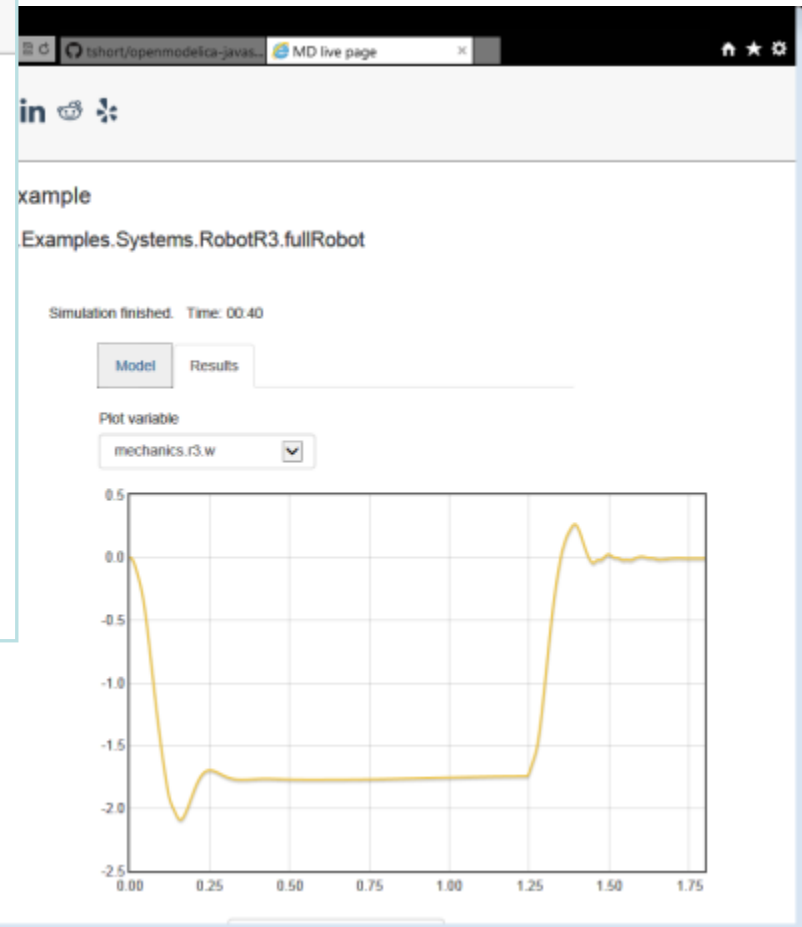
Identifier Info on Hovering

Code Outline for easy navigation within Modelica files

OpenModelica Simulation in Web Browser Client



MultiBody RobotR3.FullRobot



**OpenModelica compiles
to efficient
Java Script code which is
executed in web browser**

OMPython – Python Scripting with OpenModelica

- Interpretation of Modelica commands and expressions
- Interactive Session handling
- Library / Tool
- Optimized Parser results
- Helper functions
- Deployable, Extensible and Distributable

```
test_execute_modelica.py - C:\Users\ganan642\Desktop\test_execute_modelica.py
File Edit Format View Options Windows Help
import OMPython

OMPython.execute("loadFile('c:/OpenModelica1.8.1/testmodels/BouncingBall.mo')")
result=OMPython.execute("simulate(BouncingBall, stopTime=2, method='Euler')")
print result
OMPython.execute("plot(h)")

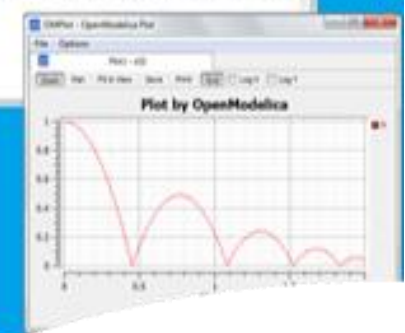
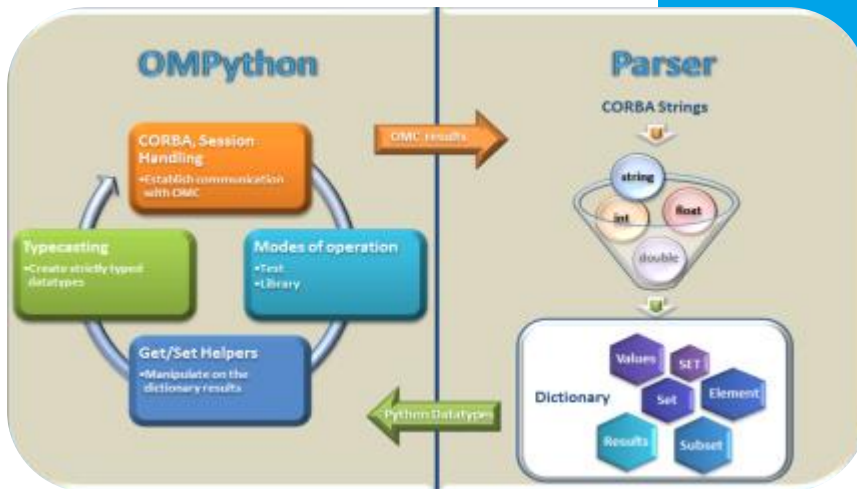
OMPython.execute("@quit()")
```

```
C:\Users\ganan642>python test_execute_modelica.py
OMC Server is up and running at file:///c:/users/ganan642/appdata/local/temp/openmodelica.objid.20120825120756188000

{'simulationoptions': {'options': {'storeInTemp': False, 'cf_lags': '...', 'simflags': '...', 'variableFilter': '...', 'noClean': False, 'outputFormat': 'mat', 'method': 'dassl', 'measureTime': False, 'stopTime': 2.0, 'startTime': 0.0, 'numberOfIntervals': 500, 'tolerance': 1e-06, 'filenamePrefix': 'BouncingBall'}, 'simulationresults': {'timecompile': 6.89815662792063, 'timeBackend': 0.0229111689831523, 'messages': '...', 'timeFrontend': 0.0245992104508437, 'timeSimulation': 0.131418166559841, 'timeTemplateS': 0.0206379911344139, 'timeSimCode': 0.00999736303670383, 'timeTotal': 7.1078098383753, 'resultFile': 'c:/users/ganan642/BouncingBall_res.mat'}}

OMC has been shutdown

C:\users\ganan642>
```



OMJulia –Julia Scripting with OpenModelica

- Interpretation of Modelica commands and expressions from Julia, transfer of data
- Control design using Julia control package together with OpenModelica
- Interactive Session handling
- Library / Tool
- Separately downloadable. be run with OpenModelica 1.13.2 or later
- Works with Jupyter notebooks

Control example with OMJulia in Jupyter notebooks

Use of Modelica + Julia in Process Systems Engineering Education

Complex models of "Seborg reactor"

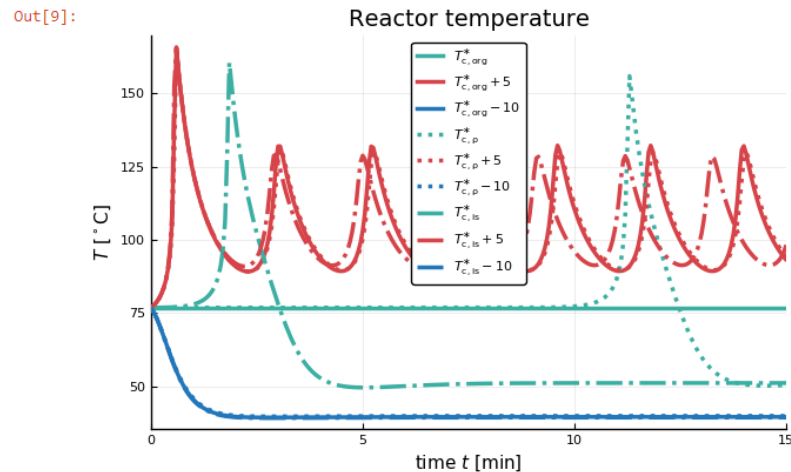
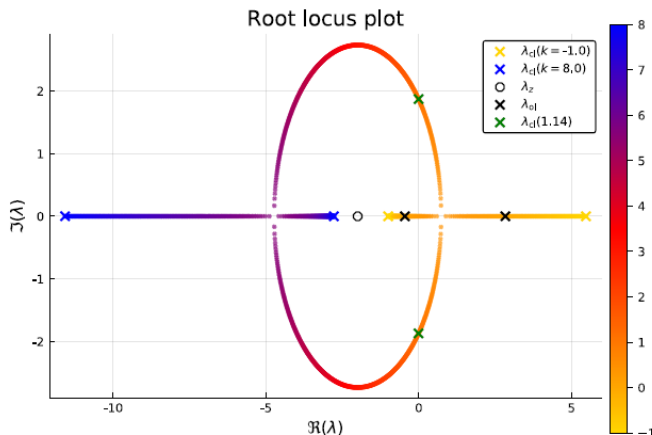
Bernt Lie*, Arunkumar Palanisamy**, Peter Fritzson**

*University of South-Eastern Norway, Norway

**University of Linköping, Sweden

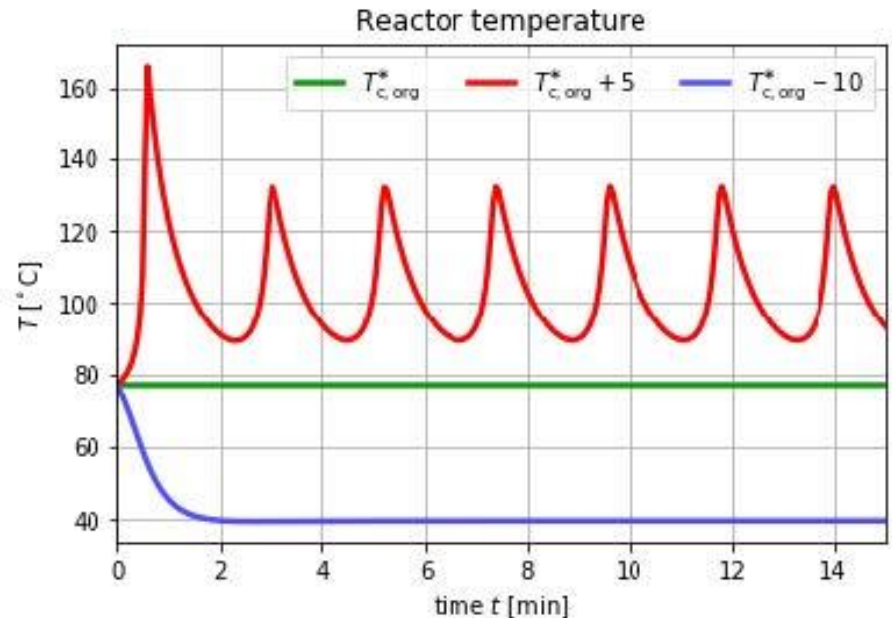
Introducing packages

```
In [1]: # Pkg.add("Plots") -- we assume that this step already has been carried out
using Plots; pyplot()
using LaTeXStrings
using DataFrames
using OMJulia
#using DifferentialEquations
```



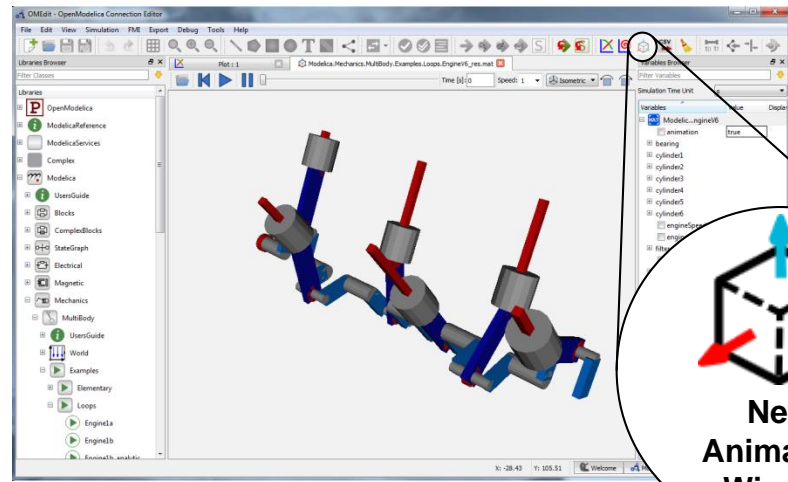
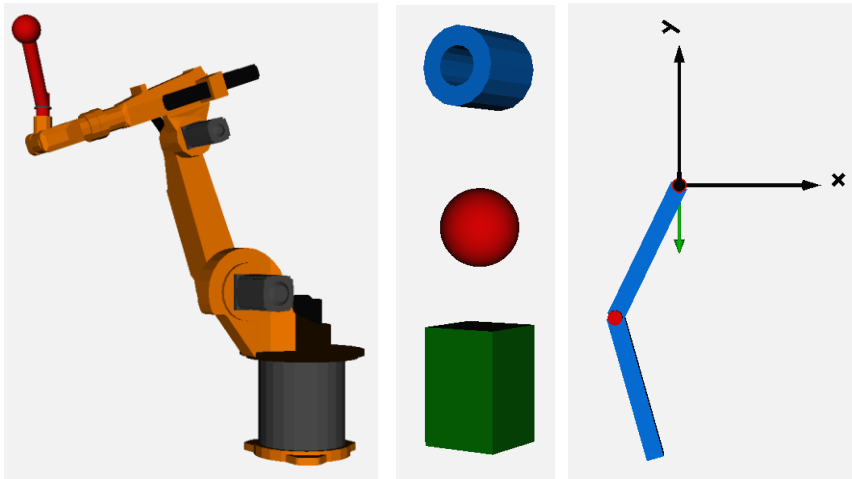
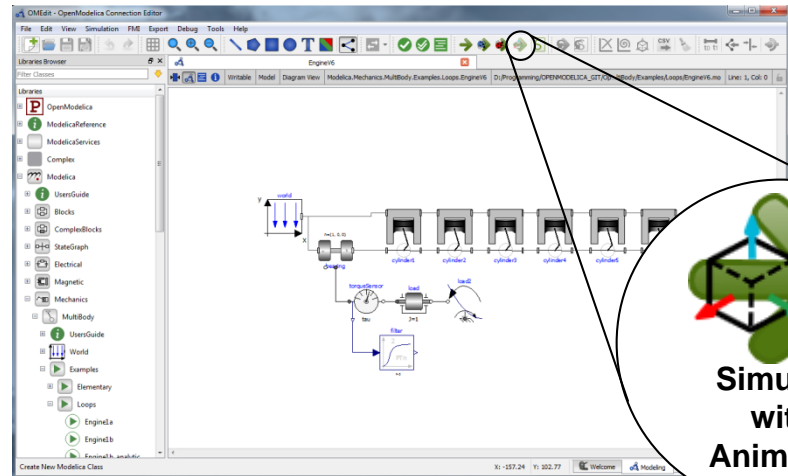
OMMatlab – Matlab Scripting with OpenModelica

- Interpretation of Modelica commands and expressions from Matlab, transfer of data
- Interactive Session handling
- Library / Tool
- Separately downloadable. be run with OpenModelica
- Similar API functions as in OMJulia and OMPython
- Can be used for control design from Matlab

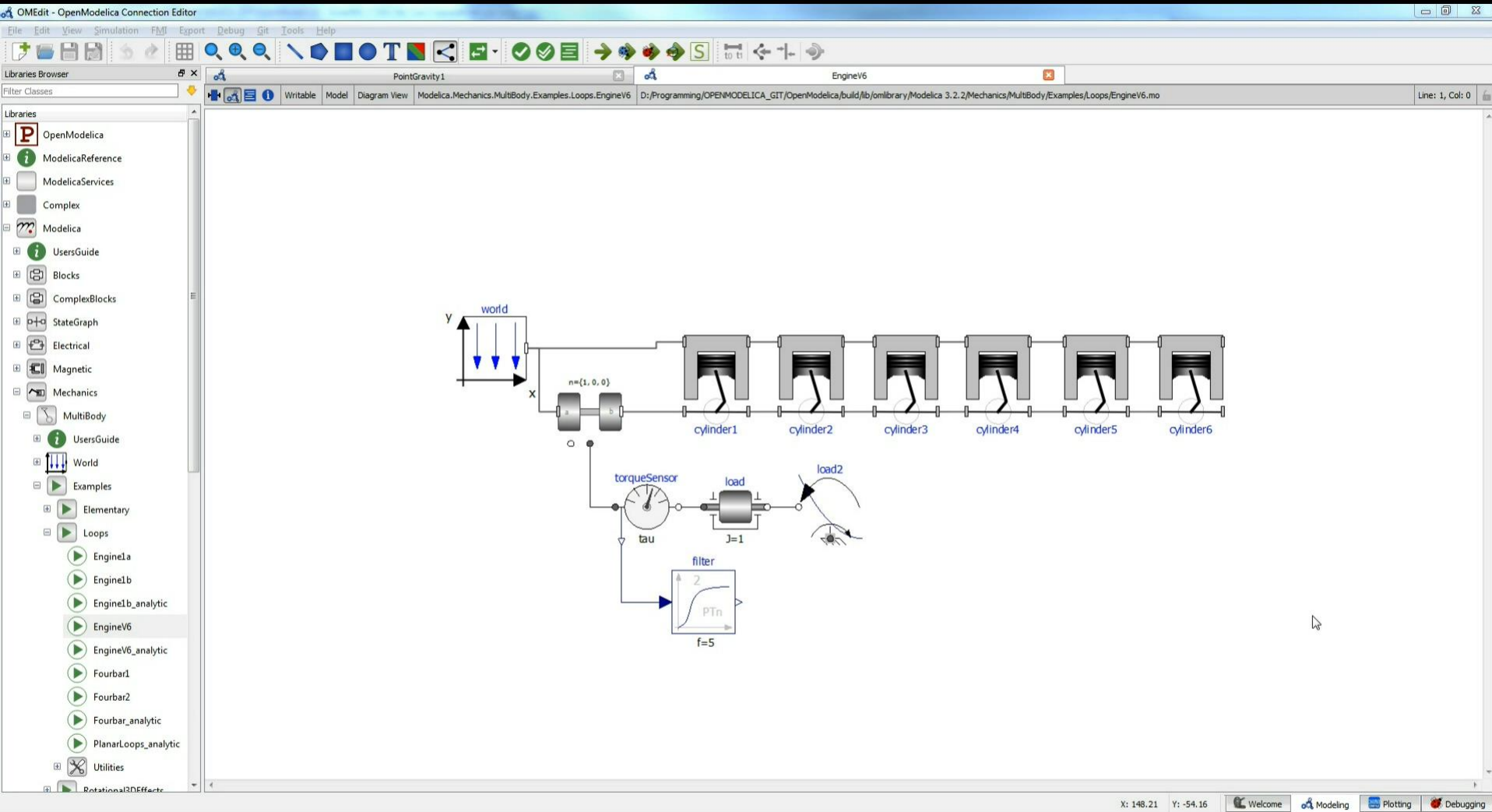


OMEdit 3D Visualization of Multi-Body Systems

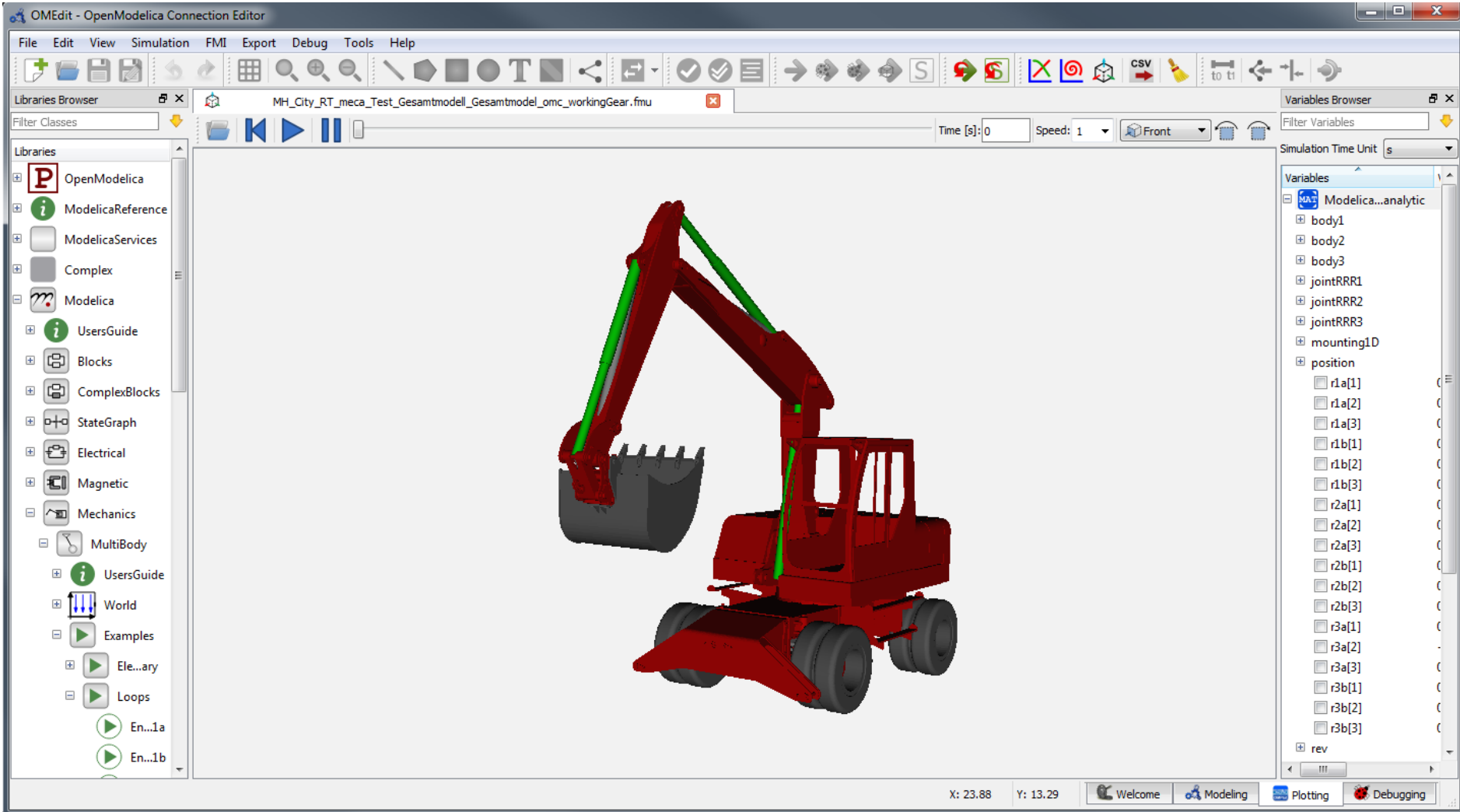
- Built-in feature of OMEdit to animate MSL-Multi-Body shapes
- Visualization of simulation results
- Animation of geometric primitives and CAD-Files



OpenModelica 3D Animation Demo (V6Engine and Excavator)

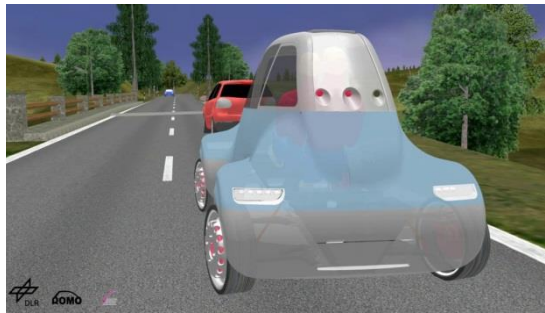
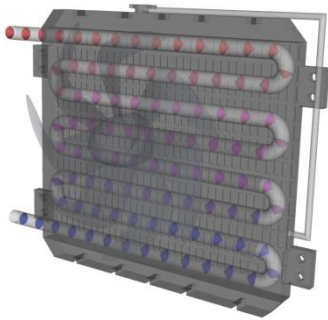


OpenModelica 3D Animation – Excavator

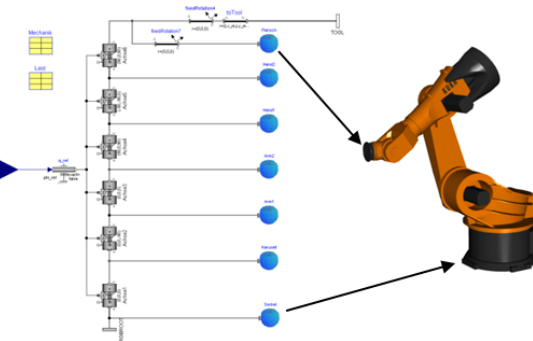
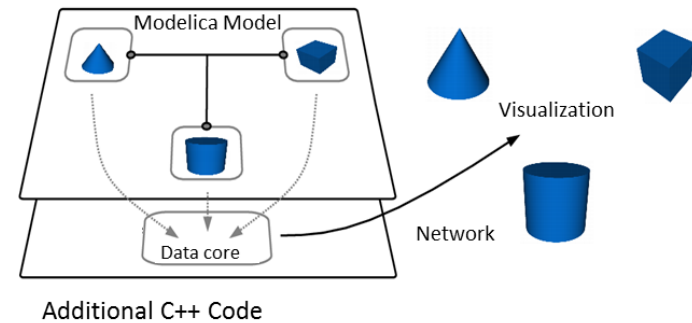


Visualization using Third-Party Libraries: DLR Visualization Library

- Advanced, model-integrated and vendor-unspecific visualization tool for Modelica models
- Offline, online and real-time animation
- Video-export function
- Commercial library, feature reduced free Community Edition exists



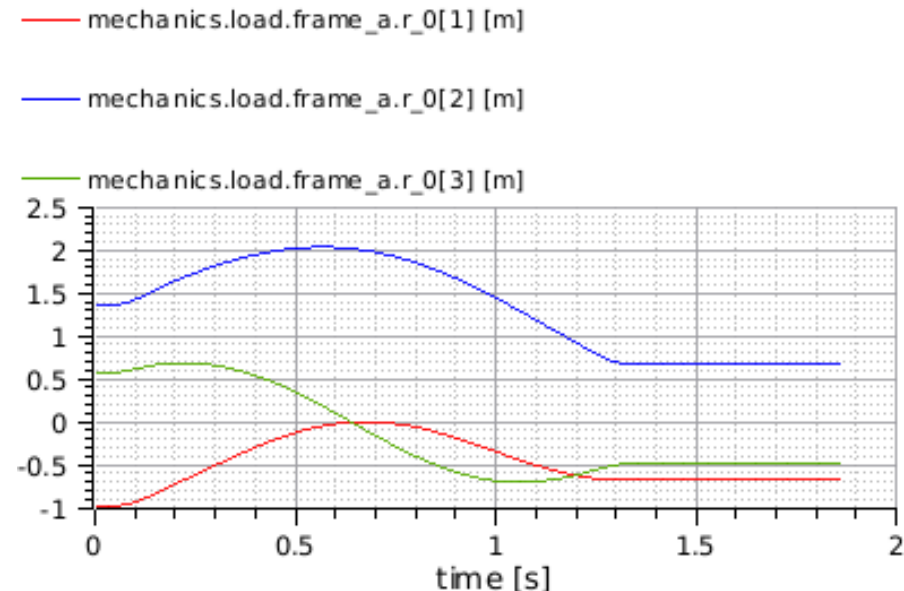
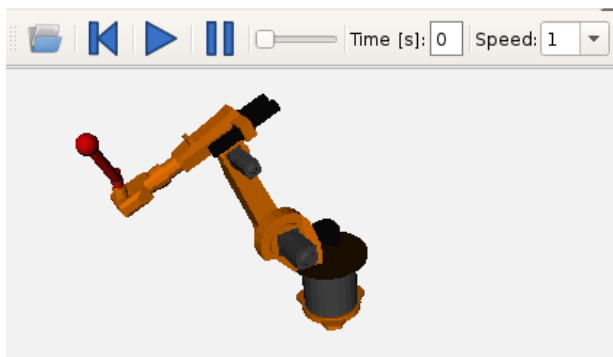
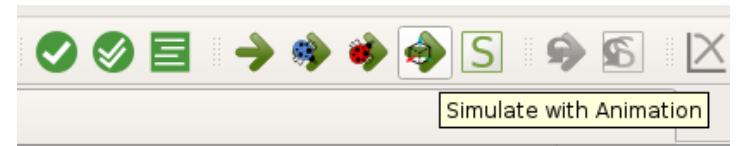
Integration of visualizer blocks into the model and Communication to an external viewer (SimVis)



Courtesy of Dr. Tobias Bellmann (DLR)

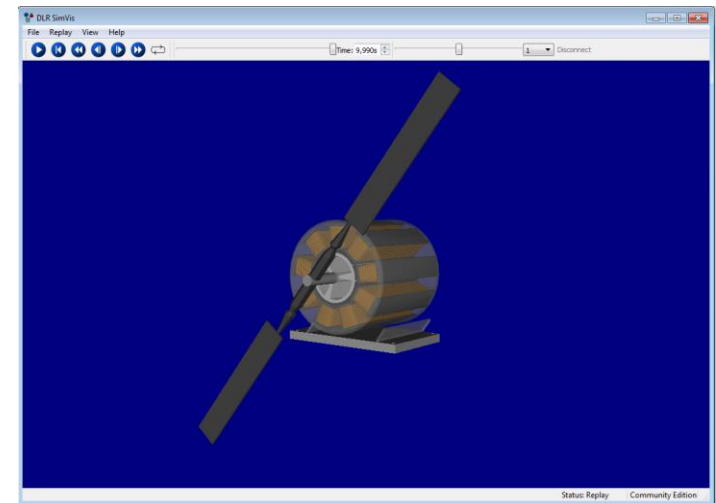
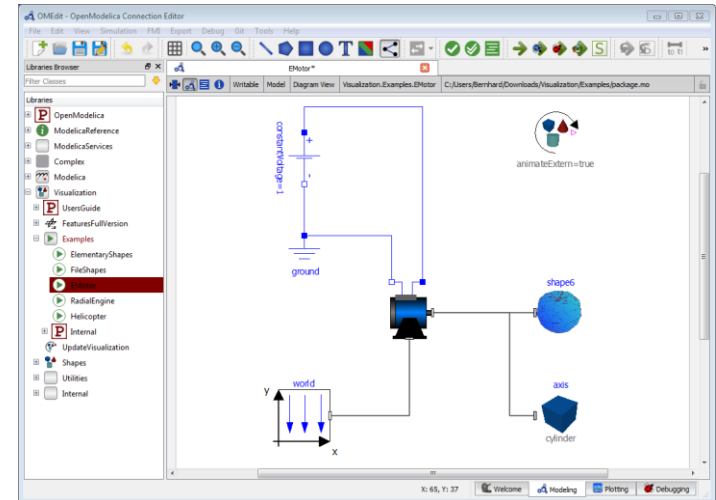
Exercise 1.2: Use 3D Visualization for Robot model

- Open the Modelica.Mechanics.MultiBody.Examples.Systems.RobotR3.fullRobot example in OMEdit
- Press Simulate with Animation
- Replay the animation
- Compare with the plot



Exercise 1.3: Visualization using the DLR Visualization Community Edition (1)

- Unpack VisualizationCommunityEdition.zip
- Open the library in OMEdit
- Simulate the EMotor example
- The DLR SimVis visualization app should start automatically
- Export the animation (File→Export Replay as Video)

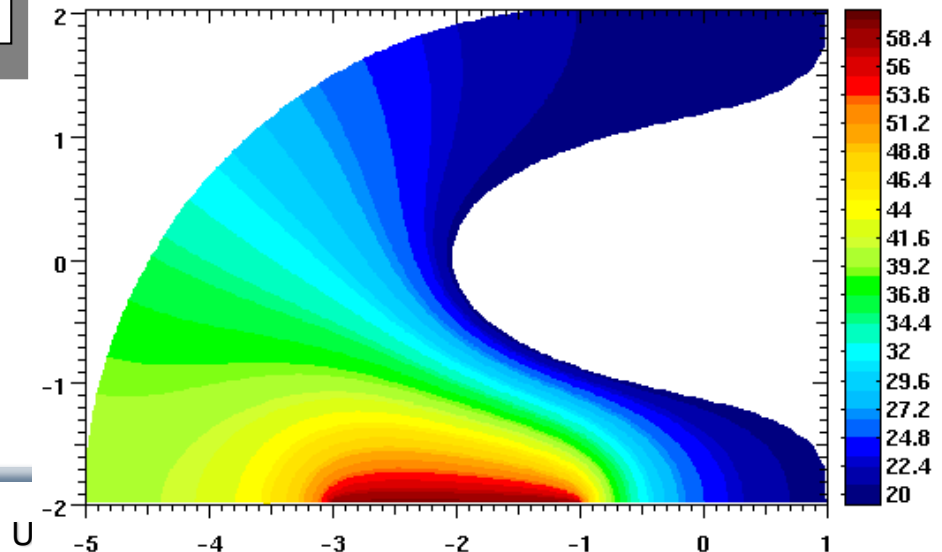
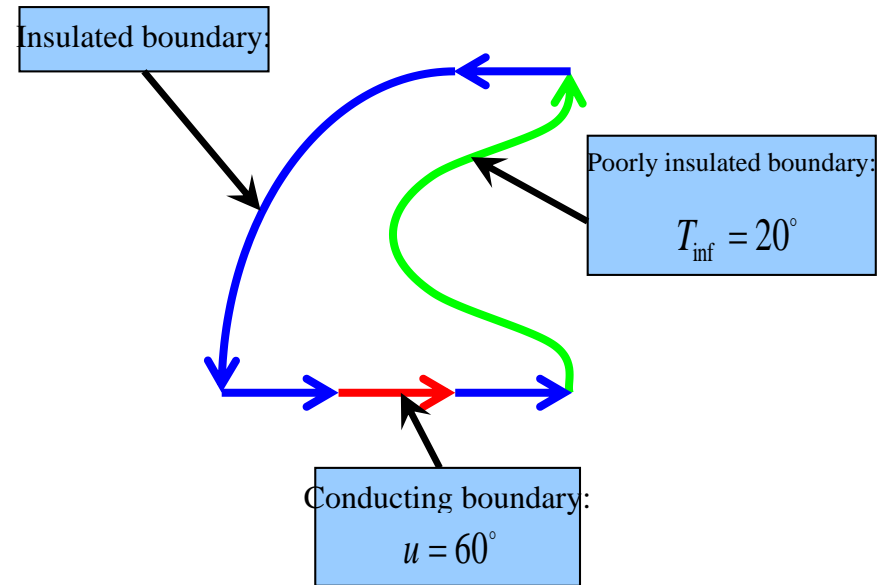


Please note: As of OpenModelica v1.14 support for the library is only partial and it is not yet as stable, fast and complete as for the Dymola tool (work in progress!)

Extending Modelica with PDEs for 2D, 3D flow problems – Research

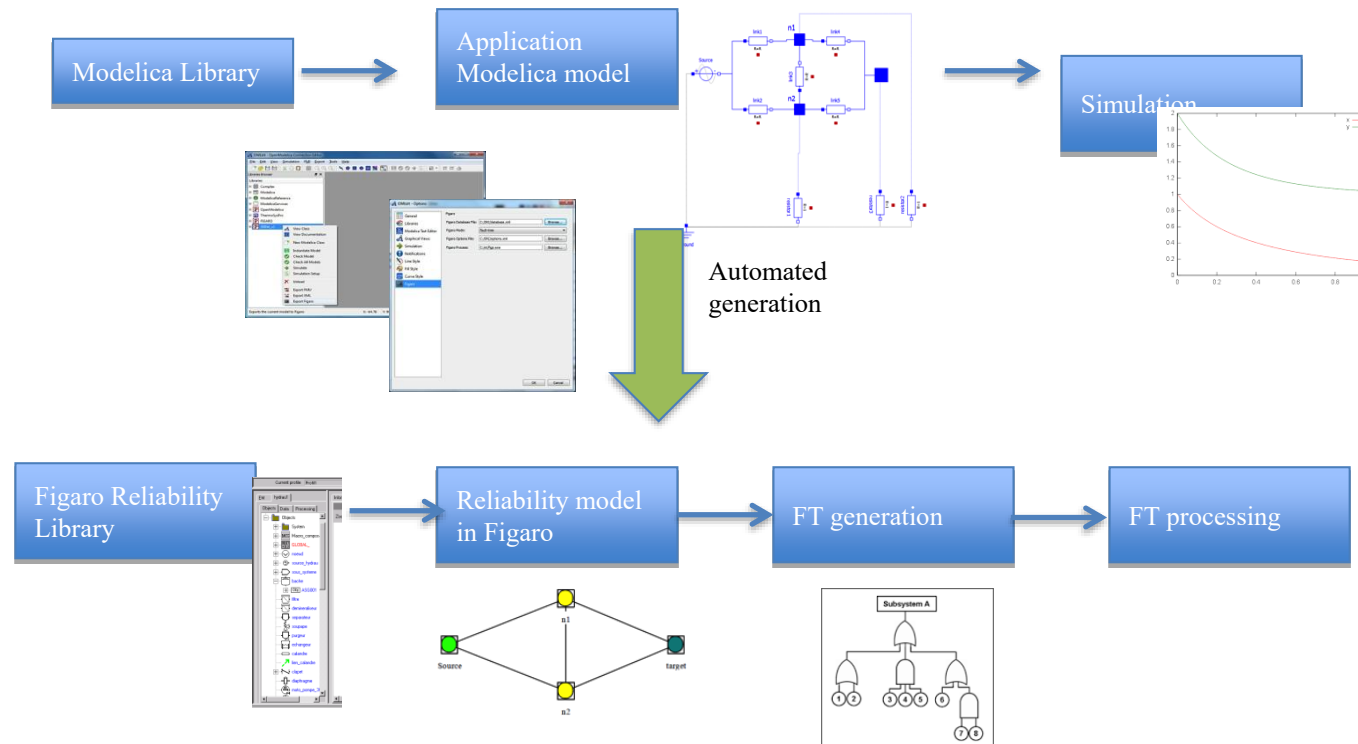
```
class PDEModel
  HeatNeumann h_iso;
  Dirichlet h_heated(g=50);
  HeatRobin h_glass(h_heat=30000);
  HeatTransfer ht;
  Rectangle2D dom;
equation
  dom.eq=ht;
  dom.left.bc=h_glass;
  dom.top.bc=h_iso;
  dom.right.bc=h_iso;
  dom.bottom.bc=h_heated;
end PDEModel;
```

Prototype in OpenModelica 2005
PhD Thesis by Levon Saldamli
www.openmodelica.org
Currently not operational



Failure Mode and Effects Analysis (FMEA) in OM

- Modelica models augmented with reliability properties can be used to generate reliability models in Figaro, which in turn can be used for static reliability analysis
- Prototype in OpenModelica integrated with Figaro tool (which is becoming open-source)



OMOptim – Optimization (1)

Model structure

Model Variables

Optimized parameters

Optimized Objectives

The screenshot displays the MinEIT software interface with the following components:

- Model Structure (Left Panel):** A list of model components including Pc, Va, Vb, Ia, Ib, Ic, Ea, Eb, Ec, coutdinvestissement, gaincouteroperationnel, EmCO2PAC1, Ca, Cb, Cc, Puissae, Puissbe, Puissce, n, na, nb, nc, OCb, OChp, coutdefonctavecPAC, TOSygmA, TOSygmB, TOSygmECS, COPECSSystem, PElecECSMax, EchIAOutCold, Sortieeffluents, echA, Sourcemod, scenarioEchA, scenarioPACA, and echB.
- Variables Table (Center Panel):** A table listing model variables with their values and descriptions. The table is highlighted with a green border.
- Optimized Variables Table (Right Panel):** A table showing optimized variables with their descriptions and optimal minimum values. The table is highlighted with a blue border.
- Scanned Variables Table (Right Panel):** A table for scanned variables with columns for Name, Description, Scan Minimum, Scan Maximum, and n. The table is currently empty.
- Optimization Objectives Table (Right Panel):** A table showing optimization objectives with their descriptions, directions, and values. The table is highlighted with a yellow border.

| Name | Value | Description |
|--------------------------------------|-------------|-------------|
| global.sourceeaudville.h | 1,18294e+06 | [J/kg] |
| global.sourceeaudville.flowPort.p | 100000 | |
| global.sourceInEchColdB.h | 1,41347e+06 | [J/kg] |
| global.sourceInEchColdB.flowPort.p | 100000 | |
| global.sourceInEchColdB.debit | 12,78 | [kg/s] |
| global.sourceEffluentsECS.h | 1,35495e+06 | [J/kg] |
| global.sourceEffluentsECS.flowPort.p | 100000 | |
| global.sourceEffluentsECS.etat | 1 | |
| global.sourceEffluentsECS.debit1 | 0 | |
| global.sourceEffluentsECS.debit | 1 | [kg/s] |
| global.sourceEffluentsB.h | 1,35495e+06 | [J/kg] |
| global.sourceEffluentsB.flowPort.p | 100000 | |
| global.sourceEffluentsB.etat | 1 | |
| global.sourceEffluentsB.debit | 1,22612 | [kg/s] |
| global.sourceEffluentsA.h | 1,35495e+06 | [J/kg] |
| global.sourceEffluentsA.flowPort.p | 100000 | |
| global.sourceEffluentsA.etat | 1 | |
| global.sourceEffluentsA.debit | 0,601234 | [kg/s] |
| global.scenariosourceEaudville.debit | 0,940001 | [kg/s] |
| global.scenariodepartB.z | 0 | |

| Name | Description | Opt. Minimum |
|---------------------------------|-------------|--------------|
| global.sourceEffluentsB.debit | [kg/s] | 0 |
| global.sourceEffluentsA.debit | [kg/s] | 0 |
| global.scenarioPACB.MySpecPcomp | | 0 |
| global.scenarioPACA.MvSpecPcomp | | 0 |

| Name | Description | Scan Minimum | Scan Maximum | n |
|------|-------------|--------------|--------------|---|
|------|-------------|--------------|--------------|---|

| Name | Description | Direction | M |
|-------------------------------|-------------|-----------|---|
| global.gaincouteroperationnel | | Maximize | 0 |
| global.coutdinvestissement | | Minimize | 0 |

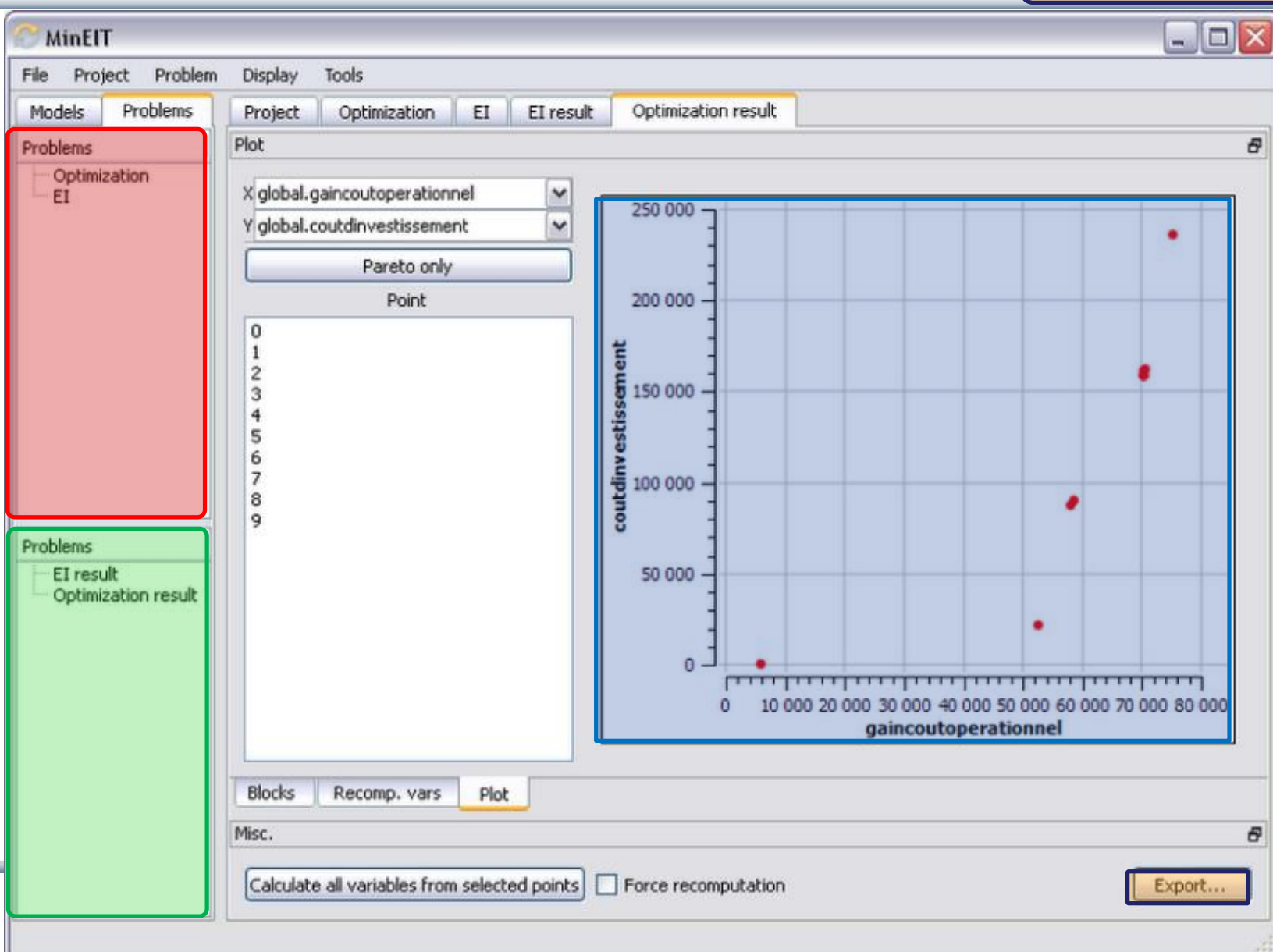
Problems

OMOptim – Optimization (2)

Solved problems

Result plot

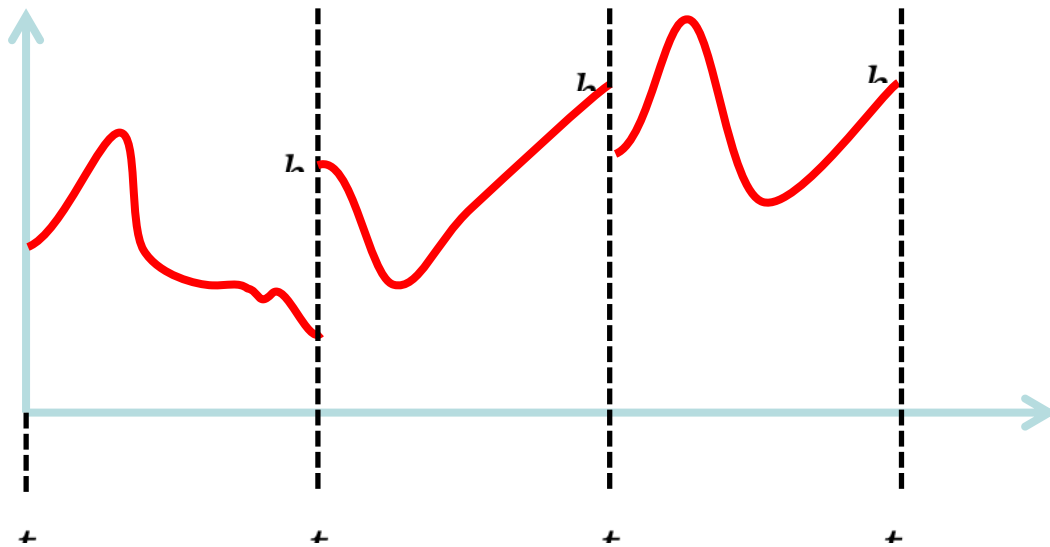
Export result data .csv



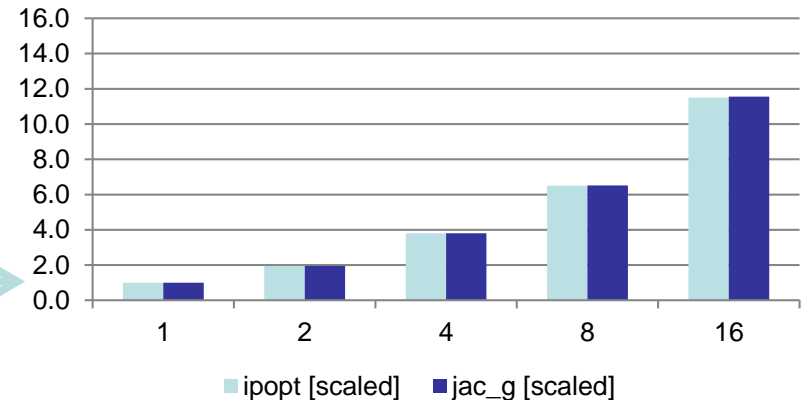
Multiple-Shooting and Collocation Dynamic Trajectory Optimization

- Minimize a goal function subject to model equation constraints, useful e.g. for NMPC
- Multiple Shooting/Collocation
 - Solve sub-problem in each sub-interval

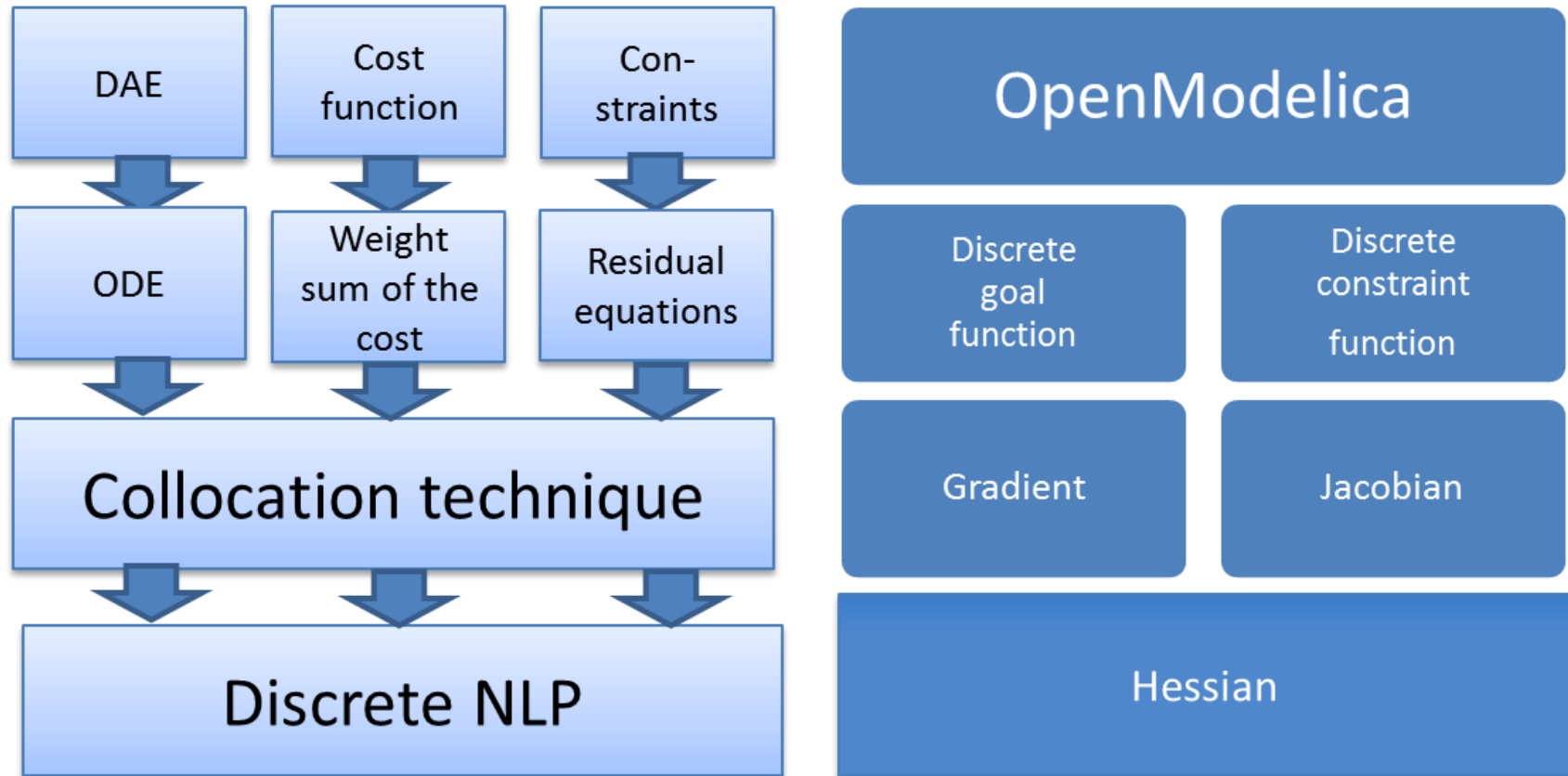
$$x_i(t_{i+1}) = h_i + \int_{t_i}^{t_{i+1}} f(x_i(t), u(t), t) dt \approx F(t_i, t_{i+1}, h_i, u_i), \quad x_i(t_i) = h_i$$



Example speedup, 16 cores:
MULTIPLE_COLLOCATION



OpenModelica Dynamic Optimization Collocation

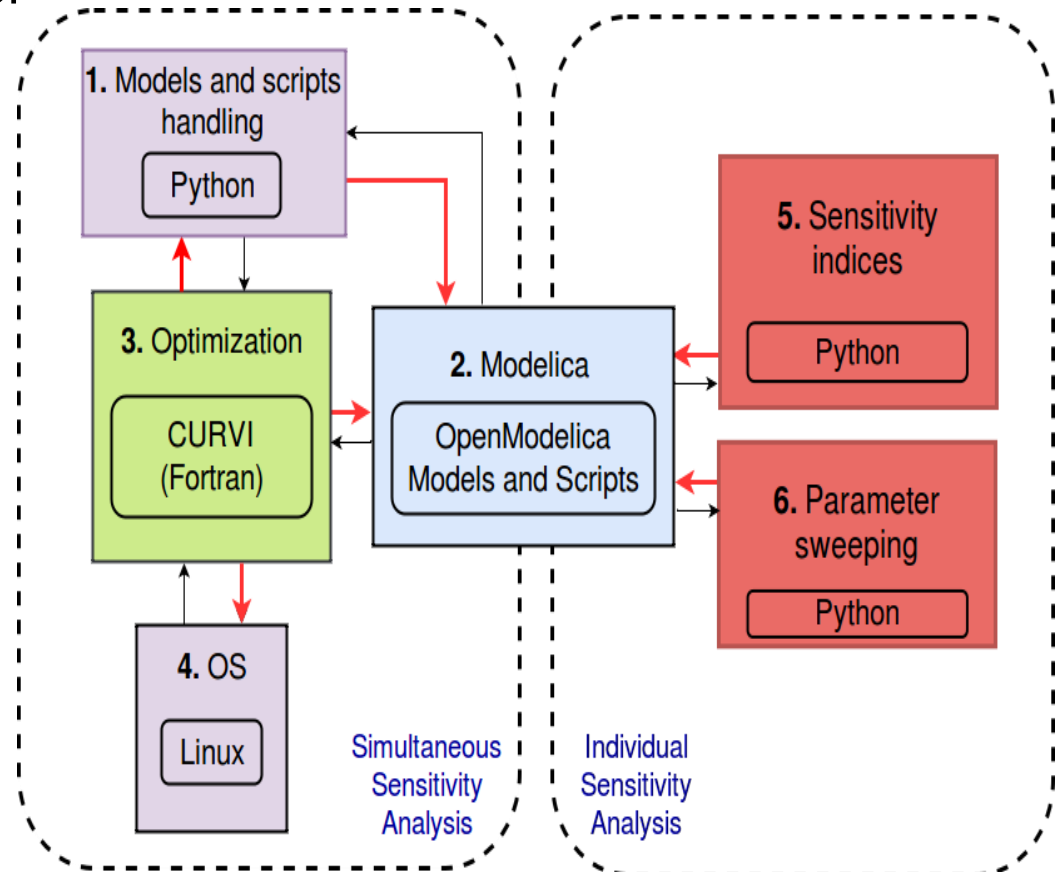
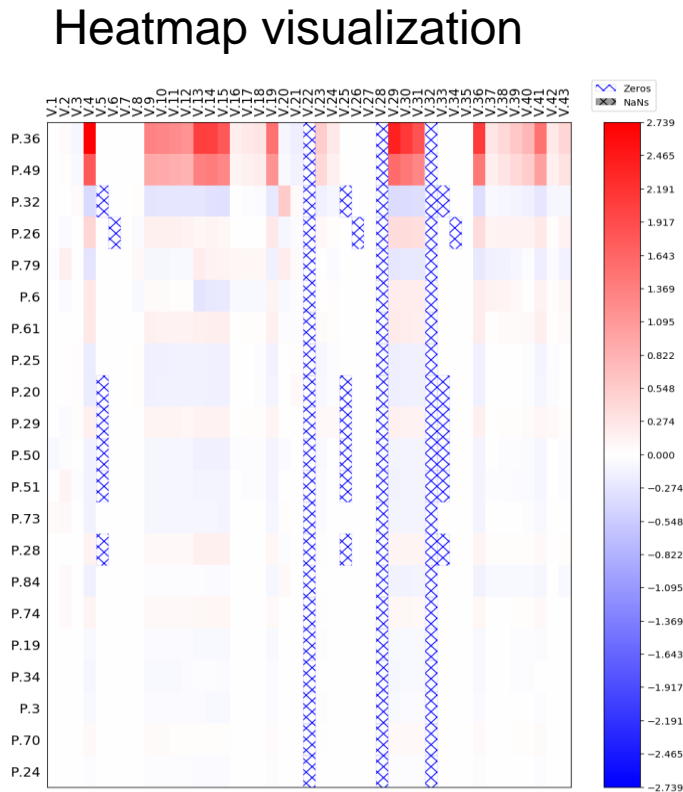


OMSens – Multi-Parameter Sensitivity Analysis

- Individual and simultaneous multi-parameter analysis
- Optimization-based simultaneous analysis
- Robust derivative free optimizer

For an exercise, see further in these slides

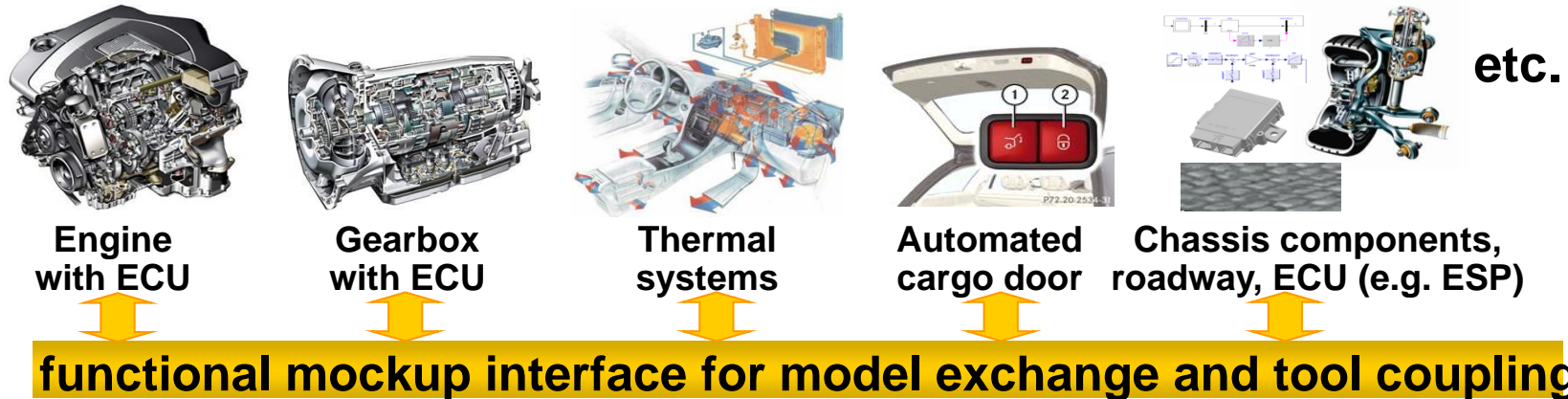
Tool architecture



OMSysIdent – System Parameter Identification

- OMSysIdent is a module for parameter estimation of behavioral models (wrapped as FMUs) on top of the OMSimulator API.
- Identification of the parameter values is typically based on measurement data
- It uses the Ceres solver (<http://ceres-solver.org/>) for the optimization task.

General Tool Interoperability & Model Exchange Functional Mock-up Interface (FMI)

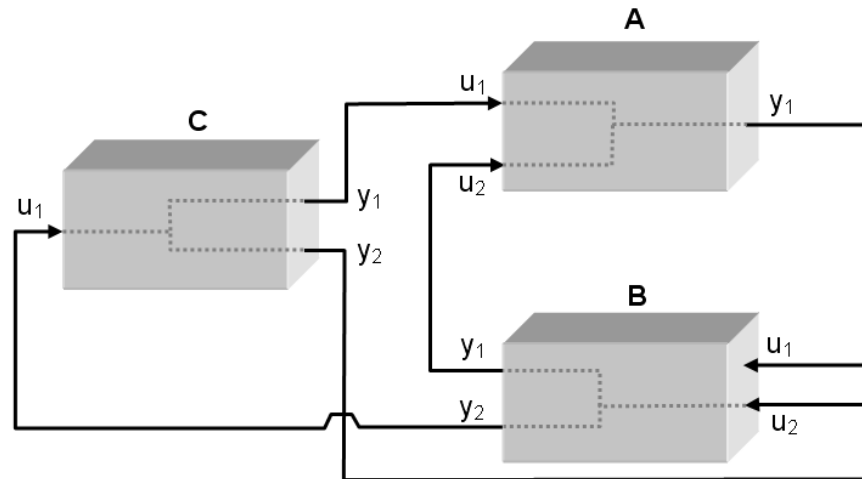


courtesy Daimler

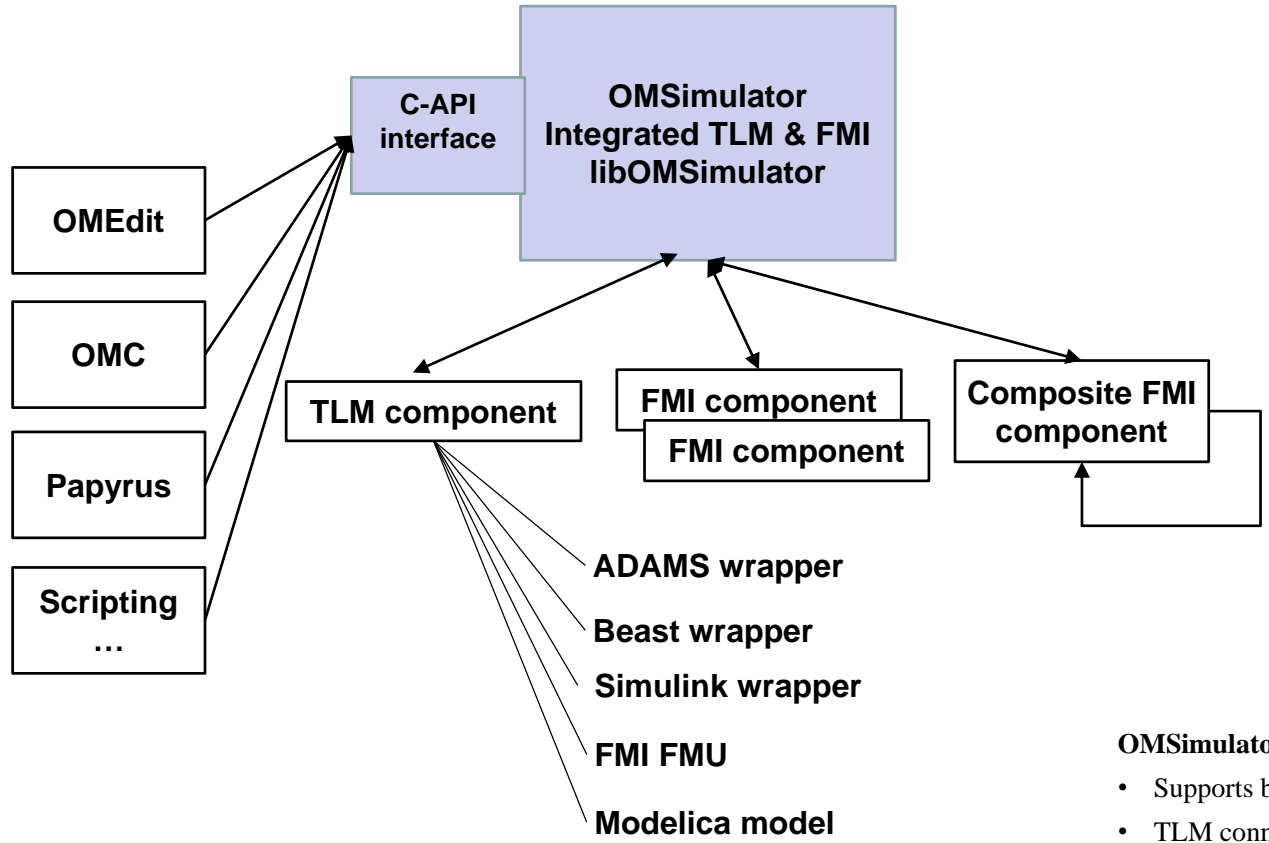
- FMI development was started by ITEA2 MODELISAR project. FMI is a Modelica Association Project now
- **Version 1.0**
- FMI for Model Exchange (released Jan 26,2010)
- FMI for Co-Simulation (released Oct 12,2010)
- **Version 2.0**
- FMI for Model Exchange and Co-Simulation (released July 25,2014)
- **> 120 tools** supporting it (<https://www.fmi-standard.org/tools>)

Functional Mockup Units

- Import and export of input/output blocks – **Functional Mock-Up Units – FMUs**, described by
 - differential-, algebraic-, discrete equations,
 - with time-, state, and step-events
- An FMU can be large (e.g. 100 000 variables)
- An FMU can be used in an embedded system (small overhead)
- FMUs can be connected together



OMSimulator – Integrated FMI and TLM-based Cosimulator/Simulator – part of OpenModelica



Main Framework Aspects

Unified co-simulation/simulation tool

- FMI 2.0 (model exchange and co-simulation)
- TLM (transition line modelling)
- Real-time and offline simulation

Standalone open source simulation tool with rich interfaces

- C/Java
- Scripting languages Python, Lua

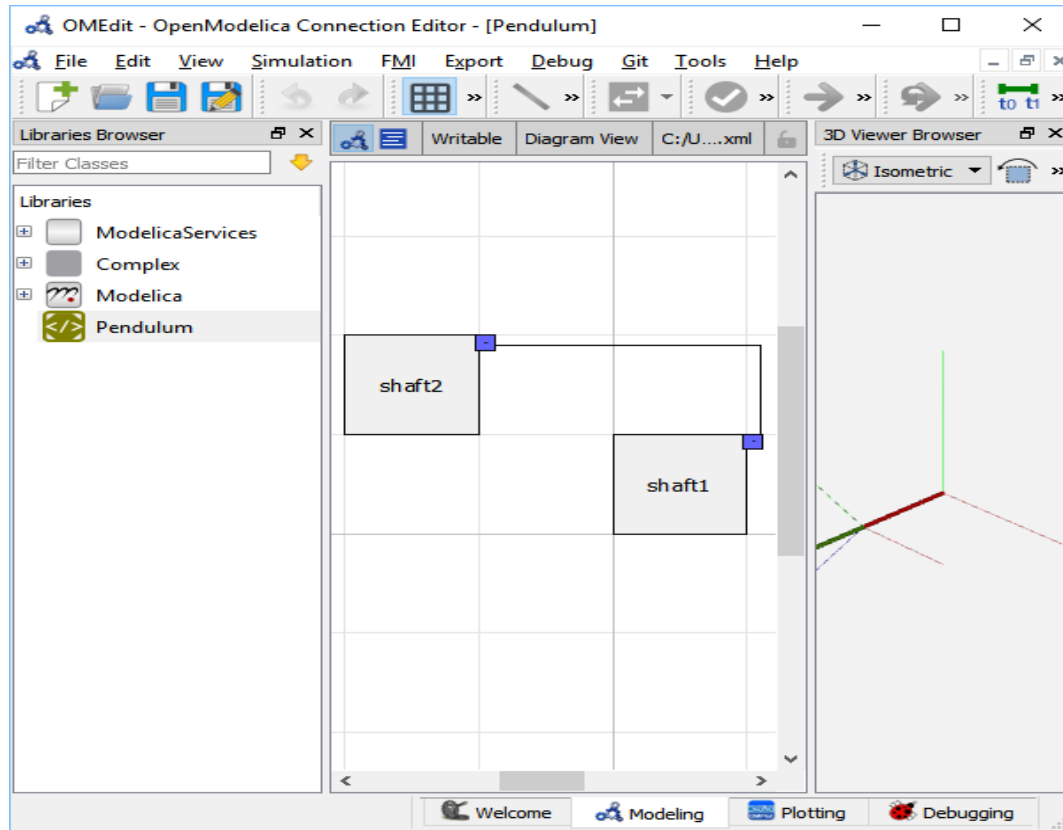
Co-simulation framework as a solid base for engineering tools

- Integration into OpenModelica/Papyrus
- Open for integration into third-party tools and specialized applications (e.g. flight simulators, optimization)

OMSimulator in OpenModelica 1.13.2

- Supports both FMI and TLM
- TLM connections are optional
- Co-simulation to multiple tools
- Composite model editor
- External API interface and scripting

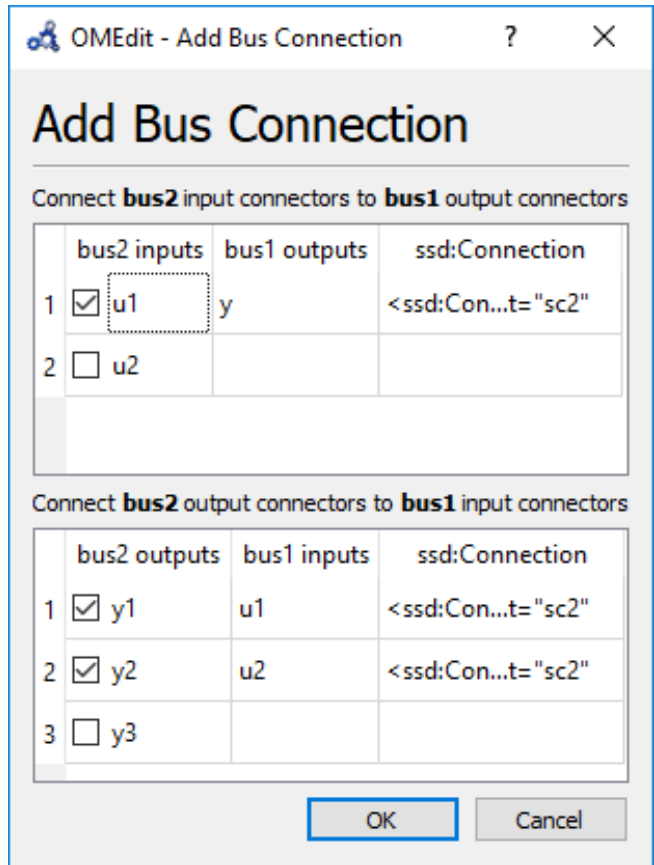
OMSimulator Composite Model Editor with 3D Viewer



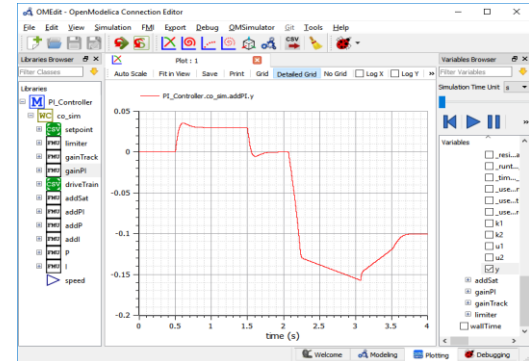
- **Composite model editor** with 3D visualization of connected mechanical model components which can be FMUs, Modelica models, etc., or co-simulated components
- **3D animation** possible
- Composite model saved as SSP XML-file
- **Support for SSP** – System Structure and Parameterization standard
- **Numerically stable** co-simulation with **TLM**

OMSimulator Simulation, SSP, and Tool Comparison

Adding SSP bus connections



FMI Simulation results in OMEdit

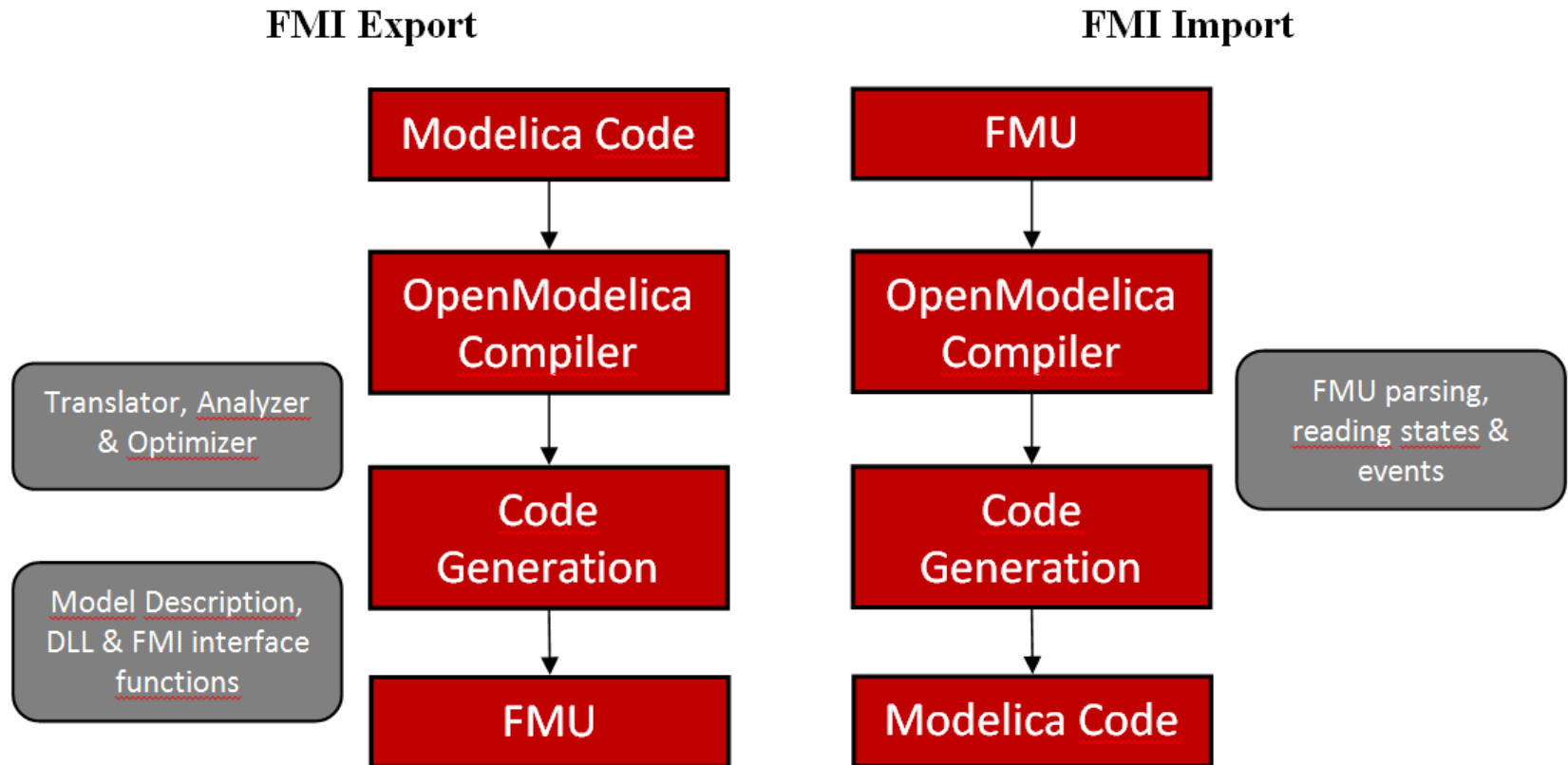


FMI Simulation Tool Comparison

| | OMSimulator | DACCOSIM | Simulink | PyFMI |
|---------------------|-----------------|-------------|-----------------|-----------------|
| Commercial | No | No | Yes | No |
| Open-source | OSMC-PL, GPL | AGPL2 | No | LGPL |
| Lookup Table | Yes | Yes | Yes | No |
| Alg. Loops | Yes | Yes | No | Yes |
| Scripting | Python, Lua | proprietary | proprietary | Python |
| GUI | Yes | Yes | Yes | No |
| SSP | Yes | No | No | No |
| platform | Linux/Win/macOS | Linux/Win | Linux/Win/macOS | Linux/Win/macOS |

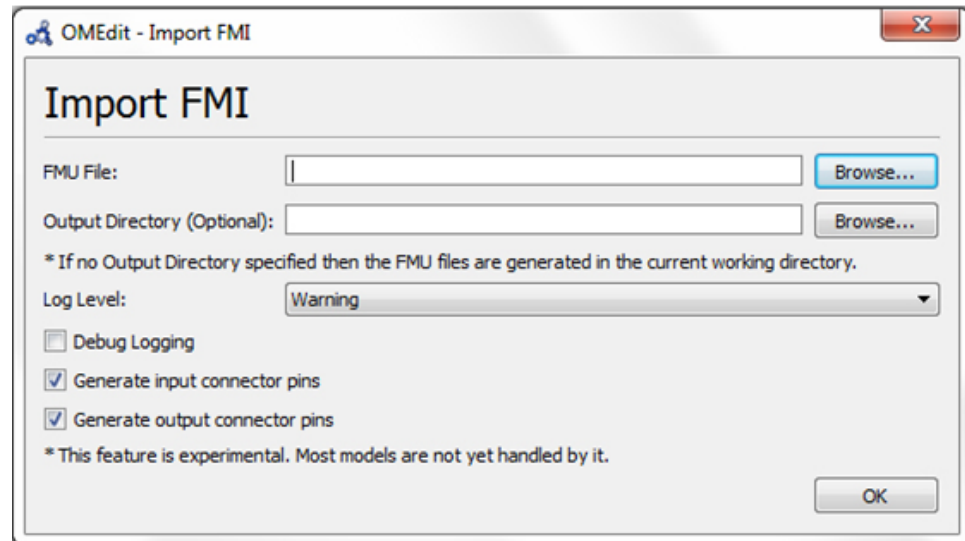
| | Dymola | PySimulator | FMI Go! | FMI Composer |
|---------------------|-------------|-------------|-----------------|-----------------|
| Commercial | Yes | No | No | Yes |
| Open-source | No | BSD | MIT | No |
| Lookup Table | Yes | Yes | Yes | Yes |
| Alg. Loops | Yes | Yes | Yes | Yes |
| Scripting | proprietary | Python | Go | No |
| GUI | Yes | Yes | No | Yes |
| SSP | No | No | Yes | Yes |
| platform | Linux/Win | Linux/Win | Linux/Win/macOS | Linux/Win/macOS |

OpenModelica Functional Mockup Interface (FMI)



FMI in OpenModelica

- Model Exchange implemented (FMI 1.0 and FMI 2.0)
- FMI 2.0 Co-simulation implemented
- The FMI interface is accessible via the **OpenModelica scripting environment**, the **OpenModelica connection editor** and the **OMSimulator** tool in OpenModelica



OpenModelica Code Generators for Embedded Real-time Code

- A **full-fledged** OpenModelica-generated source-code FMU (Functional Mockup Unit) code generator
 - Can be used to **cross-compile FMUs** for platforms with more available memory.
 - These platforms can **map** FMI inputs/outputs to analog/digital I/O in the importing FMI master.
- A very **simple code generator** generating a **small footprint** statically linked executable.
 - Not an FMU because there is no OS, filesystem, or shared objects in microcontrollers.

Code Generator Comparison, Full vs Simple

| | Full Source-code FMU targeting 8-bit AVR proc | Simple code generator targeting 8-bit AVR proc |
|--|---|--|
| Hello World (0 equations) | 43 kB flash memory 23 kB variables (RAM) | 130 B flash memory 0 B variables (RAM) |
| SBHS Board (real-time PID controller, LCD, etc) | 68 kB flash memory 25 kB variables (RAM) | 4090 B flash memory 151 B variables (RAM) |

The largest 8-bit AVR processor MCUs (Micro Controller Units) have 16 kB SRAM.

One of the more (ATmega328p; Arduino Uno) has 2 kB SRAM.

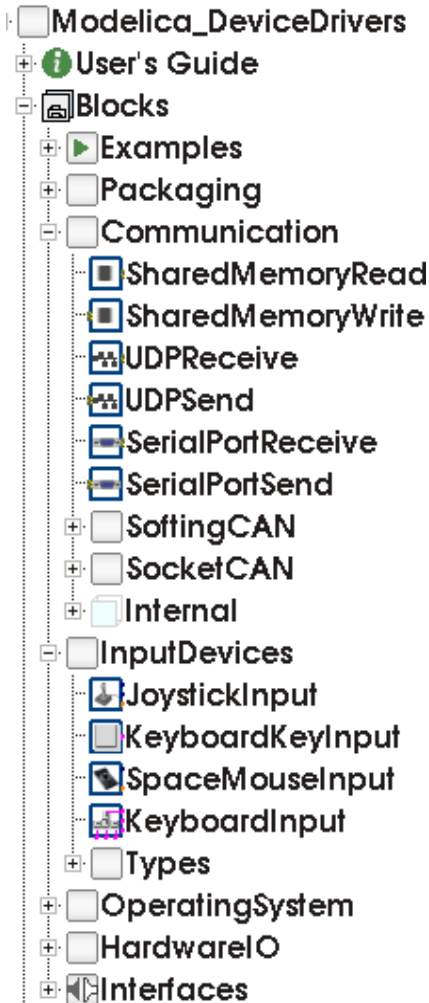
The ATmega16 we target has **1 kB SRAM available** (stack, heap, and global variables).

The Simple Code Generator

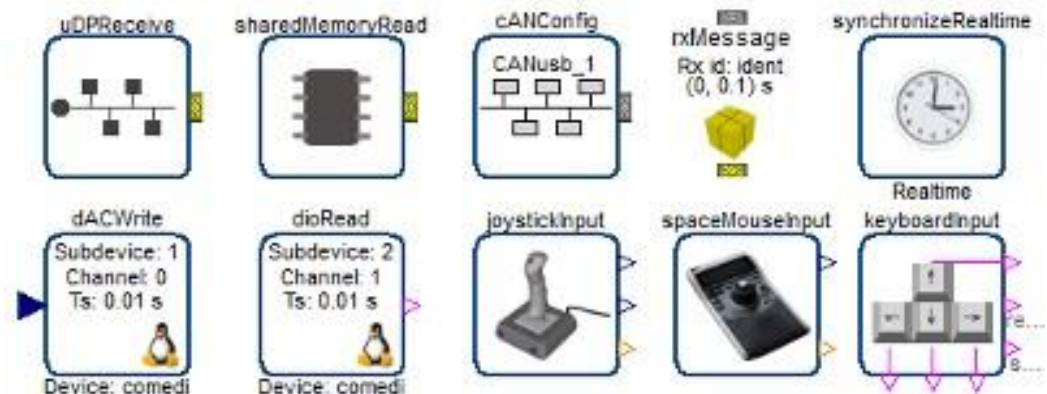
Supports only a limited Modelica subset

- No initialization (yet)
- No strongly connected components
- No events
- No functions (except external C and built-in)
- Only parts that OpenModelica can generate good and efficient code for right now (extensions might need changes in the intermediate code)
 - Unused variables are not accepted (OM usually duplicates all variables for pre() operators, non-linear system guesses, etc... but only a few of them are actually used)
- FMU-like interface (but statically linked)

Communication & I/O Devices: MODELICA_DEVICEDRIVERS Library



- **Free library** for interfacing hardware drivers
- **Cross-platform** (Windows and Linux)
- UDP, SharedMemory, CAN, Keyboard, Joystick/Gamepad
- DAQ cards for digital and analog IO (only Linux)
- Developed for **interactive real-time** simulations



https://github.com/modelica/Modelica_DeviceDrivers/

OpenModelica and Device Drivers Library

AVR Processor Support

- No direct Atmel AVR or Arduino support in the OpenModelica compiler
- **Everything is done by the Modelica DeviceDrivers library**
- **All I/O is modeled explicitly in Modelica**, which makes code generation very simple

Modelica Device Drivers Library - AVR processor sub-packages:

- IO.AVR.Analog (ADC – Analog Input)
- IO.AVR.PWM (PWM output)
- IO.AVR.Digital.LCD (HD44780 LCD driver on a single 8-pin digital port)
- OS.AVR.Timers (Hardware timer setup, used by real-time and PWM packages)
- OS.AVR.RealTime (very simple real-time synchronization; one interrupt per clock cycle; works for single-step solvers)

Use Case: SBHS (Single Board Heating System)

Single board heating system (IIT Bombay)

- Use for teaching basic control theory
- Usually controlled by serial port (set fan value, read temperature, etc)
- OpenModelica can generate code targeting the ATmega16 on the board (AVR-ISP programmer in the lower left).
Program size is 4090 bytes including LCD driver and PID-controller (out of 16 kB flash memory available).



Movie Demo, see next page!

Example – Code Generation to SHBS

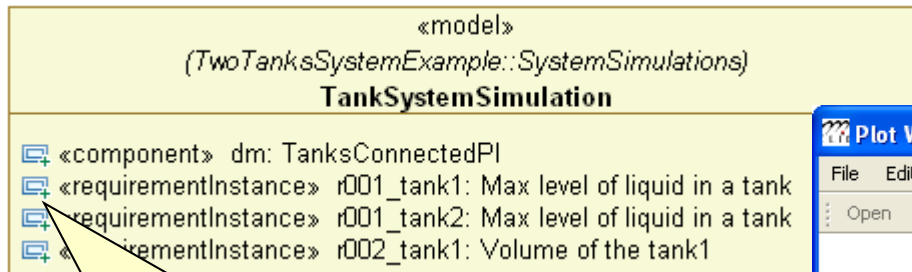


OpenModelica – ModelicaML UML Profile

SysML/UML to Modelica OMG Standardization

- ModelicaML is a UML Profile for SW/HW modeling
 - Applicable to “pure” UML or to other UML profiles, e.g. SysML
- Standardized Mapping UML/SysML to Modelica
 - Defines transformation/mapping for **executable** models
 - Being **standardized** by OMG
- ModelicaML
 - Defines graphical concrete syntax (graphical notation for diagram) for representing Modelica constructs integrated with UML
 - Includes graphical formalisms (e.g. State Machines, Activities, Requirements)
 - Which do not exist in Modelica language
 - Which are translated into executable Modelica code
 - Is defined towards generation of executable Modelica code
 - Current implementation based on the Papyrus UML tool + OpenModelica

Example: Simulation and Requirements Evaluation

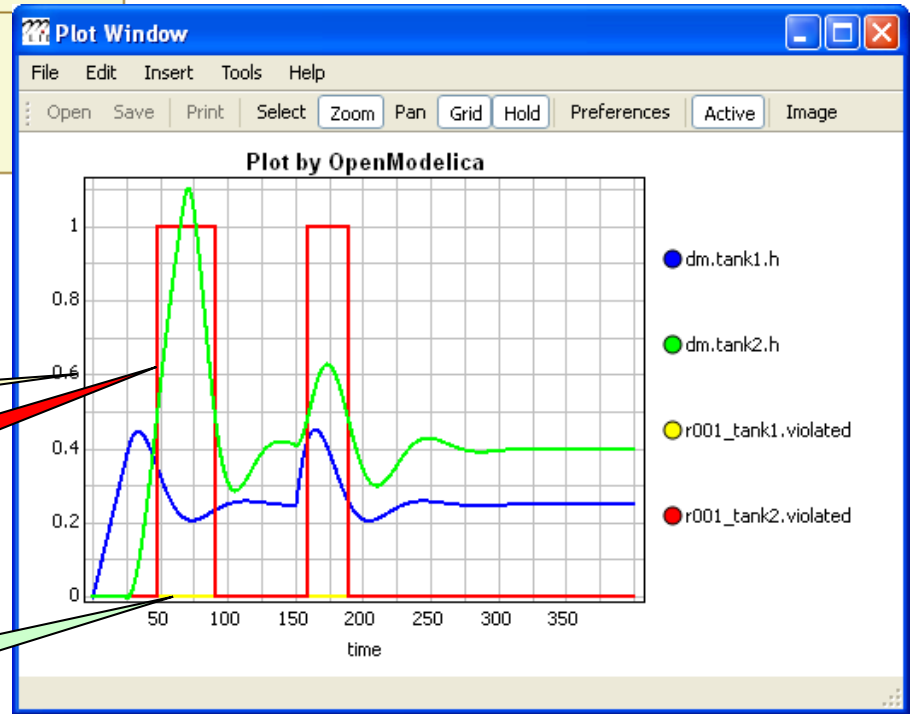


Req. 001 is instantiated 2 times (there are 2 tanks in the system)

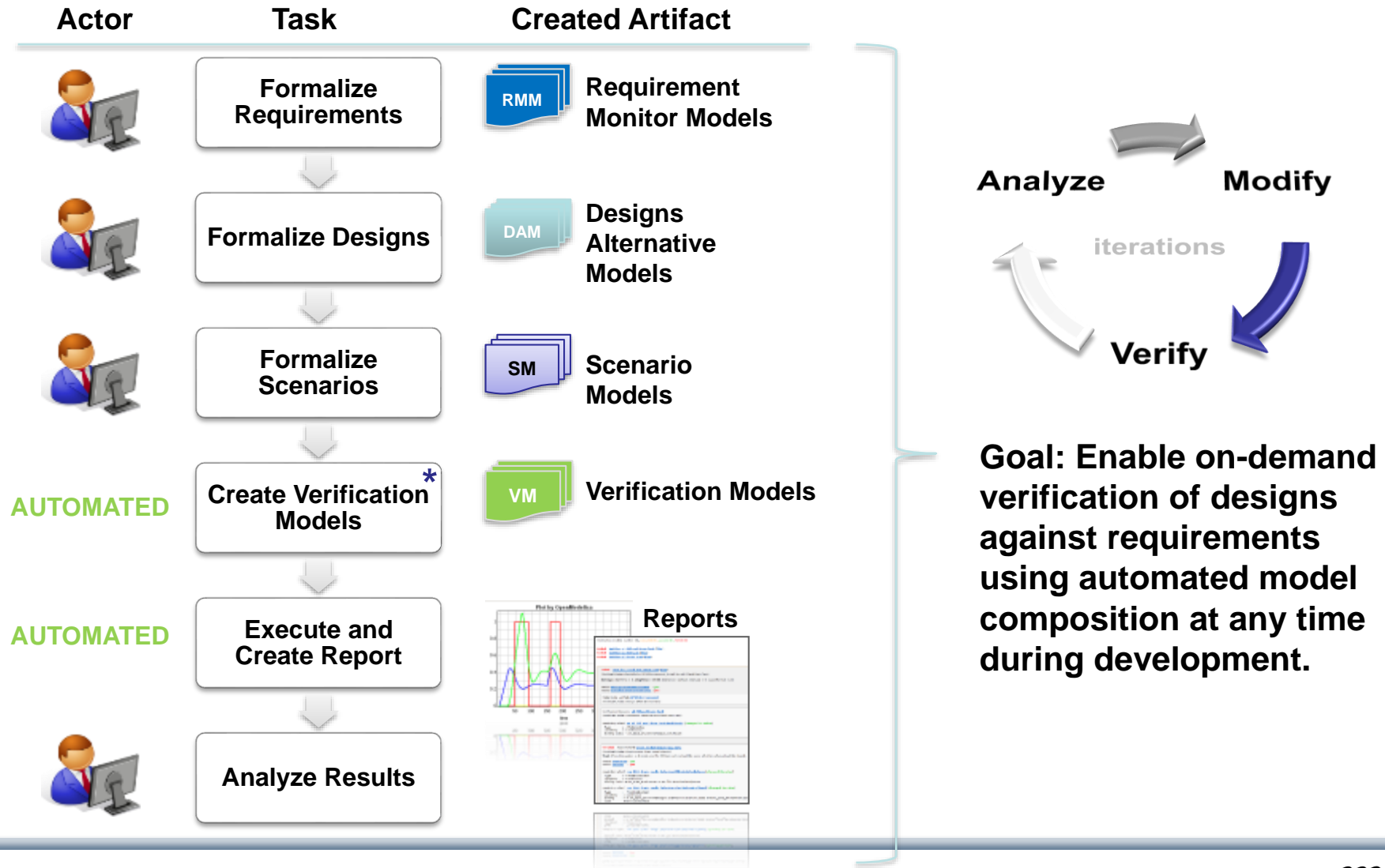
tank-height is 0.6m

Req. 001 for the tank2 is violated

Req. 001 for the tank1 is not violated



vVDR Method – virtual Verification of Designs vs Requirements



Need for Debugging Tools

Map Low vs High Abstraction Level

- A **major part** of the total **cost** of software projects is due to testing and debugging
- US-Study 2002:
Software errors cost the US economy **annually~ 60 Billion \$**
- **Problem: Large Gap in Abstraction Level**
from **Equations** to **Executable Code**
- Example error message (hard to understand)
Error solving nonlinear system 132
time = 0.002
residual[0] = 0.288956
x[0] = 1.105149
residual[1] = 17.000400
x[1] = 1.248448
...

OpenModelica MDT Algorithmic Code Debugger

The screenshot displays the Eclipse IDE interface for debugging a Modelica simulation. The main window is titled "Debug - HelloWorld/SimulationModel.mo - Eclipse SDK".

List of Stack Frames: Located in the top-left pane, it shows the current execution context. The stack includes:

- Simulation Model [Modelica Development Tooling (MDT) GDB]
- MDT
- Main Thread (stepping)
- getValueMultipliedByTwo at simulationmodel.mo:13
- eqFunction_3 at simulationmodel.mo:5
- C:\Users\adeas31\workspaceMDT\HelloWorld\SimulationModel.exe

Variables View: Located in the top-right pane, it displays the current state of variables:

| Name | Declared Type | Value | Actual Type |
|----------|---------------|-------------------------|-------------|
| inValue | Real | 1 | double |
| outValue | Real | 6.9453280720608359e-308 | double |

Code Editor: The central pane shows the source code for SimulationModel.mo:

```
model SimulationModel
  Real x(start = 1);
  Real y(start = 1);
  algorithm
    x := getValueMultipliedByTwo(x);
    y := x;
  end SimulationModel;

function getValueMultipliedByTwo
  input Real inValue;
  output Real outValue;
  algorithm
    outValue := inValue * 2;
  end getValueMultipliedByTwo;
```

Outline: Located in the bottom-right pane, it provides a hierarchical view of the code structure:

- getValueMultipliedByTwo
 - inValue (Real - IN)
 - outValue (Real - OUT)
- SimulationModel
 - x
 - y

Output View: Located in the bottom-left pane, it is currently empty, indicating that no output has been captured during the debug session.

The OpenModelica MDT Debugger (Eclipse-based) Using Japanese Characters

Debug - trunk/testsuite/mosfiles-nosim/QuotedFunction.mo - Eclipse SDK

File Edit Navigate Search Run Project Window Help

Correct Indentation Build project

Debug MDT

MDT GDB [Modelica Development Tooling (MDT) GDB]

MDT

Main Thread (stepping)

- オープンモデリッカー・ロックス at quotedfunction.mo:5
- Ceval_cevalCallFunction at Ceval.mo:1294
- Ceval_ceval at Ceval.mo:318
- Interactive_evaluateExpr at Interactive.mo:935
- Interactive_evaluateExprToStr at Interactive.mo:985
- Interactive_evaluate2 at Interactive.mo:507
- Interactive_evaluateToStdOut at Interactive.mo:329
- Interactive_evaluateToStdOut at Interactive.mo:333
- Interactive_evaluateToStdOut at Interactive.mo:333

Variables Breakpoints

| Name | Declared Type | Value |
|---------------------|---------------|-----------------|
| ◆ キャン・ザー・デバガー・シー・ミー | Real | 1.5 |
| ◆ イエス・イット・キャン | Real | -4.836697827222 |

moGenerator.c Main.mo Util.mo System_omc.cpp systemimpl.c QuotedFunction.mo 31

```
function 'オープンモデリッカー・ロックス'  
  input Real 'キャン・ザー・デバガー・シー・ミー';  
  output Real 'イエス・イット・キャン';  
algorithm  
  'イエス・イット・キャン' := sin('キャン・ザー・デバガー・シー・ミー');  
end 'オープンモデリッカー・ロックス';
```

Console Tasks Problems Executables

MDT GDB [Modelica Development Tooling (MDT) GDB] C:\OpenModelica\trunk\testsuite\bootstrapping\main.exe

```
true  
""
```

OpenModelica Equation Model Debugger

The screenshot displays the OMEdit - Transformational Debugger interface, which is used for debugging equation models. It is divided into three main panes:

- Variables View:** Shows a tree structure of variables (e.g., frame, boxBody1, body, frame_a, R, T) and their definitions in equations. It includes filters for case sensitivity and regular expressions, and buttons for expanding or collapsing all variables.
- Equations View:** Displays a list of equations with their indices and types. Below this, it shows the 'Defines' and 'Depends' relationships between variables, along with 'Equation Operations' such as solving, scalarizing, simplifying, inlining, and substituting.
- Source View:** Shows the source code of the model, with line numbers and comments. The code includes relationships between quantities of frame_a and frame_b, and uses the Frames library for planar rotations and absolute rotations.

Showing equation transformations of a model:

$0 = y + \text{der}(x * \text{time} * z); z = 1.0;$

(1) substitution:

$y + \text{der}(x * (\text{time} * z))$
 \Rightarrow
 $y + \text{der}(x * (\text{time} * 1.0))$

(2) simplify:

$y + \text{der}(x * (\text{time} * 1.0))$
 \Rightarrow
 $y + \text{der}(x * \text{time})$

(3) expand derivative (symbolic diff):

$y + \text{der}(x * \text{time})$
 $\Rightarrow y + (x + \text{der}(x) * \text{time})$

(4) solve:

$0.0 = y + (x + \text{der}(x) * \text{time})$
 \Rightarrow
 $\text{der}(x) = ((-y) - x) / \text{time}$
 $\text{time} \langle > 0$

Mapping run-time error to source model position

Transformations Browser – EngineV6 Overview (11 116 equations in model)

The screenshot displays the OMEdit - Transformational Debugger interface. The top bar shows the file path: `/tmp/OpenModelica_marsj/OMEdit/Modelica.Mechanics.MultiBody.Examples.Loops.EngineV6_info.xml`. The interface is divided into several panels:

- Variables Browser:** Shows a tree view of variables. The `phi` variable is selected. Below it, a list of variables is shown with their comments, line numbers, and locations.
- Defined in Equations:** A table showing the definition of the selected variable. It lists the index (587), type (initial), and equation (nonlinear).
- Used In Equations:** A table showing where the variable is used. It lists the index, type (regular), and equation (assignment).
- Equations Browser:** A table showing the equations defined in the model. It lists the index, type, and equation.
- Source Browser:** Shows the source code of the model. The code is in a text editor, showing the definition of the `phi` variable and the relationships between quantities of frame_a and frame_b.

The Source Browser shows the following code:

```
386 Connections.branch(frame_a.R,  
387 frame_b.R);  
388 assert(cardinality(frame_a) > 0,  
389 "Connector frame_a of Revolute  
390 joint is not connected");  
391 assert(cardinality(frame_b) > 0,  
392 "Connector frame_b of Revolute  
393 joint is not connected");  
394  
395 angle = phi_offset + phi;  
396 w = der(phi);  
397 a = der(w);  
398  
399 // relationships between quantities  
400 of frame_a and of frame_b  
401 frame_b.r_theta = frame_a.r_theta;  
402  
403 if rooted(frame_a.R) then  
404 R_rel = Frames.planarRotation(e,  
405 phi_offset + phi, w);  
406 frame_b.R =  
407 Frames.absoluteRotation(frame_a.R,  
408 R_rel);  
409 frame_a.f = -  
410 Frames.resolve(R_rel, frame_b.f);  
411 frame_a.t = -  
412 Frames.resolve(R_rel, frame_b.t);  
413 else  
414 R_rel = Frames.planarRotation(-e,  
415 phi_offset + phi, w);  
416 frame_a.R =  
417 Frames.absoluteRotation(frame_b.R,  
418 R_rel);  
419 frame_b.f = -  
420 Frames.resolve(R_rel, frame_a.f);  
421 frame_b.t = -  
422 Frames.resolve(R_rel, frame_a.t);  
423 end if;  
424  
425 // d'Alemberts principle  
426 tau = -frame_b.t*e;  
427  
428 // Connection to internal
```

Equation Model Debugger on Siemens Model (Siemens Evaporator test model, 1100 equations)

The screenshot displays the OMEdit - Transformational Debugger interface. The main window shows the source code of a Siemens Evaporator test model. A callout box with a black border and white background points to a specific line of code in the source browser. The callout text reads: "Pointing out the buggy equation y = u1/u2; that gives division by zero". The source browser shows the following code snippet:

```
184 equation
185   y = u1/u2;
186   annotation (
187     Documentation(info="<html>
188       <p>
189         This block computes the output <b>y</b> (element-wise)
190         by <i>dividing</i> the corresponding elements of
191         the two inputs <b>u1</b> and <b>u2</b>:
192       </p>
193       <pre>
194         y = u1 / u2;
195       </pre>
196     </html>"),
197     Icon(coordinateSystem(
198       preserveAspectRatio=true,
199       extent={{-100,-100},{100,100}},
200       initialScale=0.1), graphics={
201       Line(points={{50,0},{100,0}}, color={0,0,127}),
202       Line(points={{-30,0},{30,0}}),
203       Ellipse(fillPattern=FillPattern.Solid, extent={{-5,20},
204       {5,30}}),
205       Ellipse(fillPattern=FillPattern.Solid,
206       extent={{-5,-30},{5,-20}}),
207       Ellipse(lineColor={0,0,127}, extent={{-50,-50},
208       {50,50}}),
209       Text(
210         lineColor={0,0,255},
211         extent={{-150,110},{150,150}},
212         textString="y = u1/u2;")
213     })
214   )
```

The interface also shows a Variables Browser on the left, an Equations Browser at the bottom left, and a Source Browser on the right. The Equations Browser shows a list of equations, with the equation 'Evap.Hex.LnQ2.division2.u2' highlighted. The Source Browser shows the code for this equation, which is the one pointed to by the callout box.

Debugging Example – Detecting Source of Chattering (excessive event switching) causing bad performance

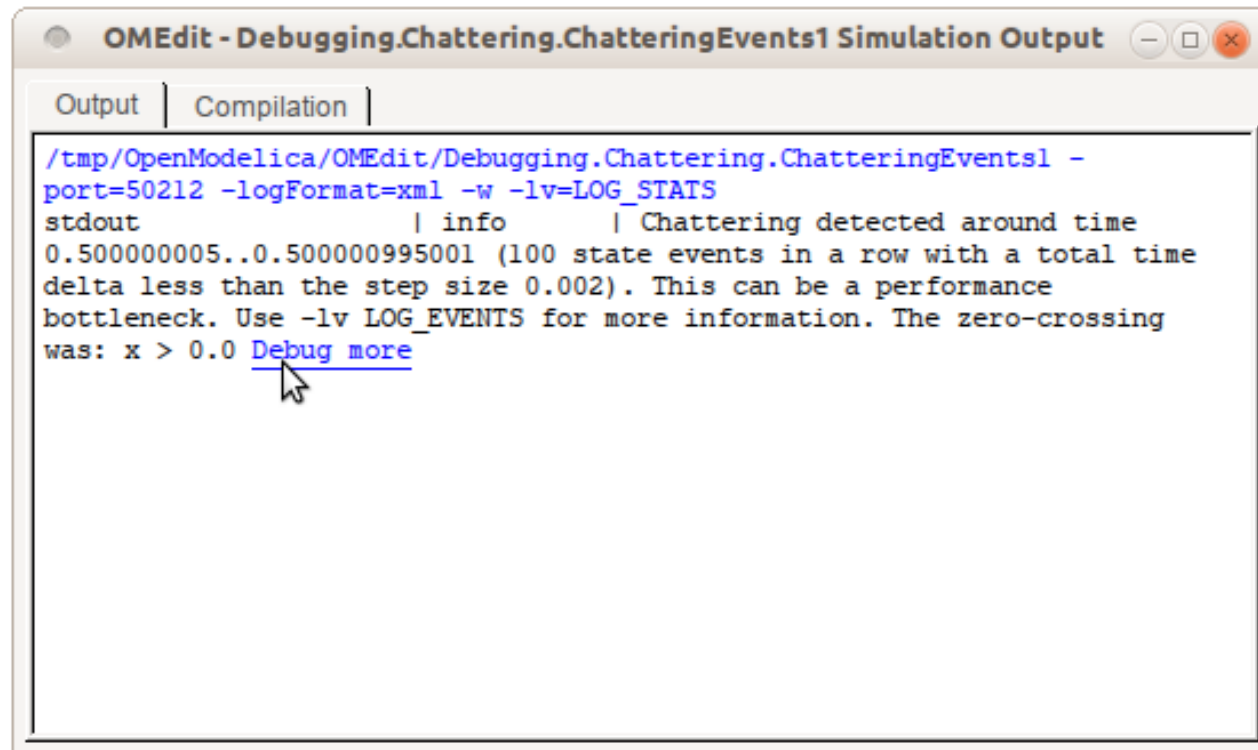
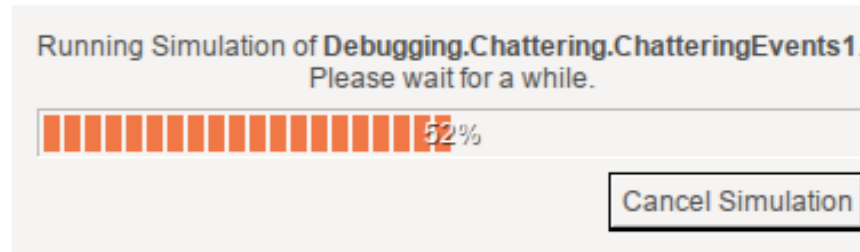
The screenshot displays the OMEdit - Transformational Debugger interface. The main window shows the source code of a model, with the following code visible:

```
1 within ;
2 package Debugging "Test
  cases for debugging of
  declarative models"
3
4 package Chattering "Models
  with chattering behaviour"
5 model ChatteringEvents1
6   "Exhibits chattering
  after t = 0.5, with
  generated events"
7   Real x(start=1,
  fixed=true);
8   Real y;
9   Real z;
  equation
  z = if x > 0 then -1
  else 1;
12  y = 2*z;
13  der(x) = y;
14  annotation
  (Documentation(info="<html>
15  <p>After t = 0.5, chattering
  takes place, due to the
  presence of the right
  hand side of the
  equation.</p>
  <p>Chattering can be
  detected because lots of
  tightly spaced events are
  generated. The feedback to
  the user should allow to
  identify the equation from
  which the zero crossing
  function that generates the
  events originates.</p>
16  </html>"),
  experiment(StopTime=1));
18 end ChatteringEvents1;
19
20 model ChatteringEvents2
21   "Exhibits chattering
  after t = 0.422, with
  generated events"
```

The equation `z = if x > 0 then -1 else 1;` is highlighted in blue. A black arrow points from this equation to the text `equation z = if x > 0 then -1 else 1;` overlaid on the image. The interface also shows the Variables Browser, Equations Browser, and Variable Operations panels.

equation
z = if x > 0 then -1 else 1;
y = 2*z;

Error Indication – Simulation Slows Down



Performance Profiling for Faster Simulation

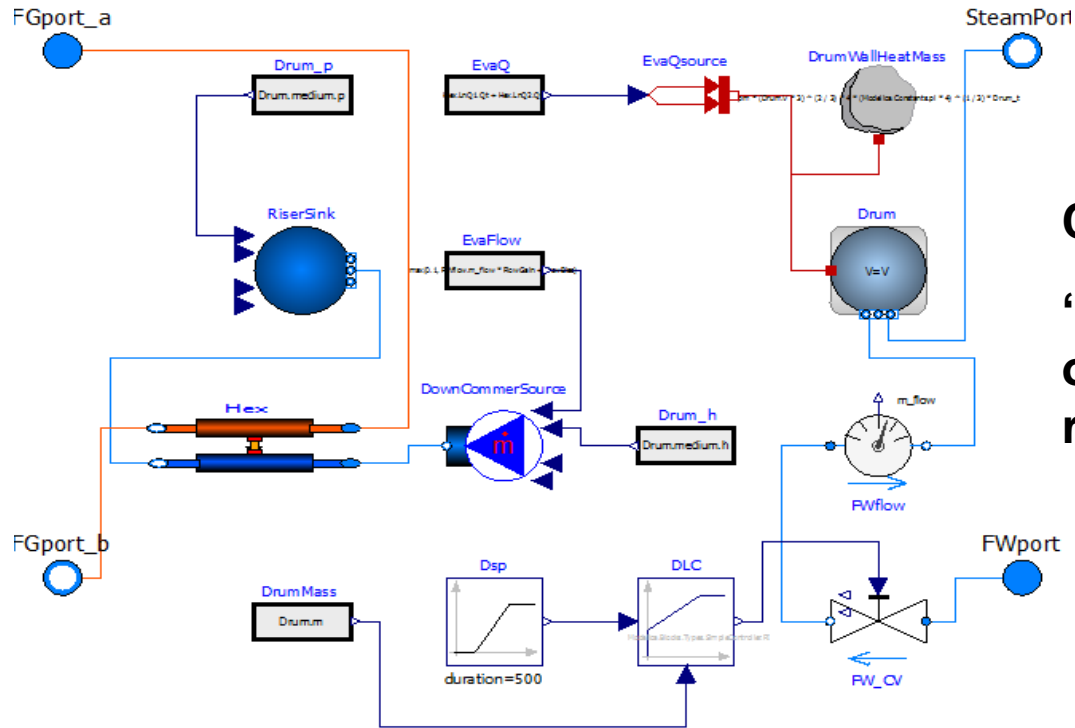
(Here: Profiling all equations in MSL 3.2.1 DoublePendulum)

- Measuring **performance** of equation blocks to find bottlenecks
 - Useful as input before model simplification for real-time applications
- Integrated with the debugger to **point out the slow equations**
- Suitable for **real-time profiling** (collect less information), or a complete view of all equation blocks and function calls

Performance profiling DoublePendulum:

| Equations Browser | | | | | | | Defines |
|-------------------|---------|-------------------------------|---------|----------|----------|----------|--|
| Index | Type | Equation | Executi | Max time | Time | Fraction | Variable |
| + 876 | regular | linear, size 2 | 4602 | 0.000501 | 0.0134 | 75.7% | damper.a_rel revolute2.frame_b.f[2] |
| - 836 | regular | (assignment) ...evolute2.phi) | 1534 | 2.57e-05 | 0.000377 | 2.12% | |
| - 840 | regular | (assignment) ...mper.phi_rel) | 1534 | 1.38e-05 | 0.000237 | 1.33% | |
| - 837 | regular | (assignment) ...evolute2.phi) | 1534 | 8.38e-06 | 0.000235 | 1.32% | |
| - 841 | regular | (assignment) ...mper.phi_rel) | 1534 | 8.48e-06 | 0.000192 | 1.08% | |
| - 849 | regular | (assignment) ...mper.phi_rel) | 1534 | 8.04e-06 | 0.000146 | 0.824% | |

Performance Profiling of Siemens Drum Boiler Model with Evaporator



Conclusion from the evaluation:
“...the profiler makes the process of performance optimization radically shorter.”

ABB Industry Use of OpenModelica FMI 2.0 and Debugger

- ABB OPTIMAX® provides advanced model based control products for power generation and water utilities



- ABB: *“ABB uses several compatible Modelica tools, including OpenModelica, depending on specific application needs.”*
- ABB: *“OpenModelica provides outstanding debugging features that help to save a lot of time during model development.”*

Exercise 1.2 – Equation-based Model Debugger

In the model ChatteringEvents1, chattering takes place after $t = 0.5$, due to the discontinuity in the right hand side of the first equation. Chattering can be detected because lots of tightly spaced events are generated. The debugger allows to identify the (faulty) equation that gives rise to all the zero crossing events.

```
model ChatteringEvents1
  Real x(start=1, fixed=true);
  Real y;
  Real z;
equation
  z = noEvent(if x > 0 then -1 else 1);
  y = 2*z;
  der(x) = y;
end ChatteringNoEvents1;
```

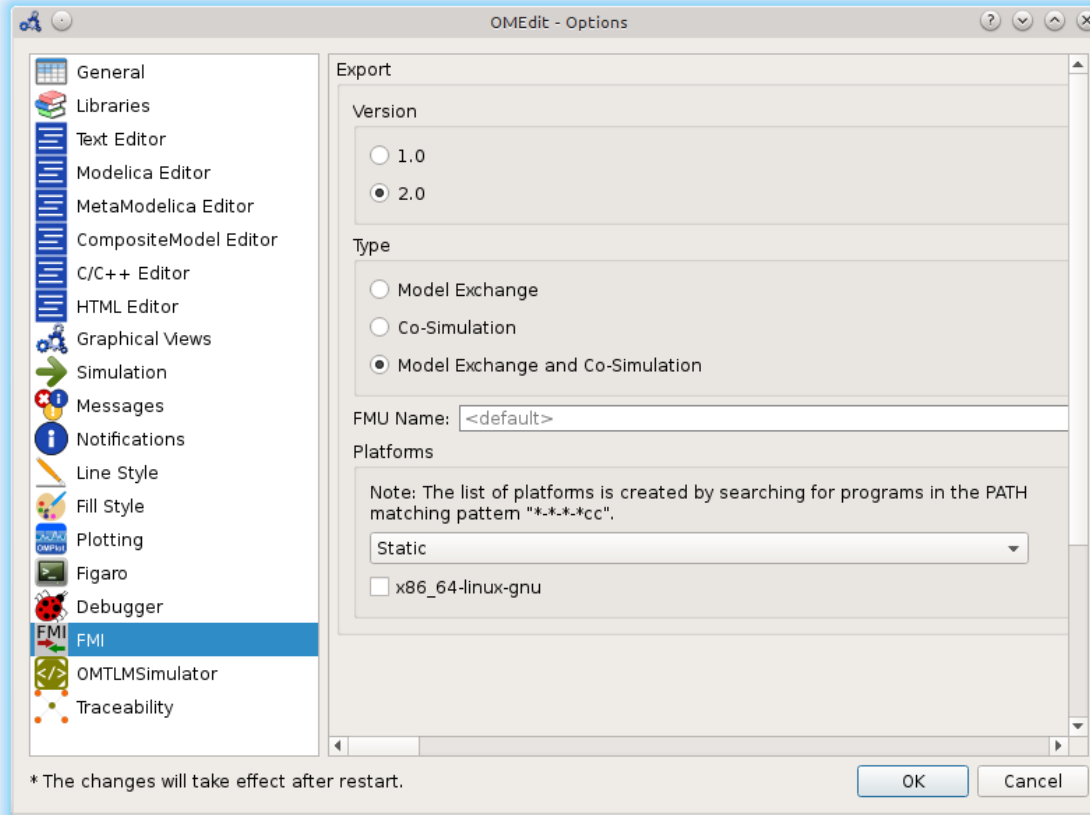
Uses 25% CPU

| | | | | |
|-------------------------|---------|----|---------|---|
| acrotray.exe *32 | petfr27 | 00 | 976 K | A |
| AdobeARM.exe *32 | petfr27 | 00 | 1,136 K | A |
| Bootcamp.exe | petfr27 | 00 | 1,448 K | B |
| conhost.exe | petfr27 | 00 | 1,300 K | C |
| csrss.exe | | 00 | 3,000 K | |
| DCSHelper.exe *32 | petfr27 | 00 | 660 K | D |
| Debugging.Chattering... | petfr27 | 25 | 1,436 K | D |
| dllhost.exe | petfr27 | 00 | 2,224 K | C |

- Switch to OMEdit text view (click on text button upper left)
- Open the Debugging.mo package file using OMEdit
- Open subpackage Chattering, then open model ChatteringEvents1
- Simulate in debug mode
- Click on the button Debug more (see prev. slide)
- Possibly start task manager and look at CPU. Then click stop simulation button

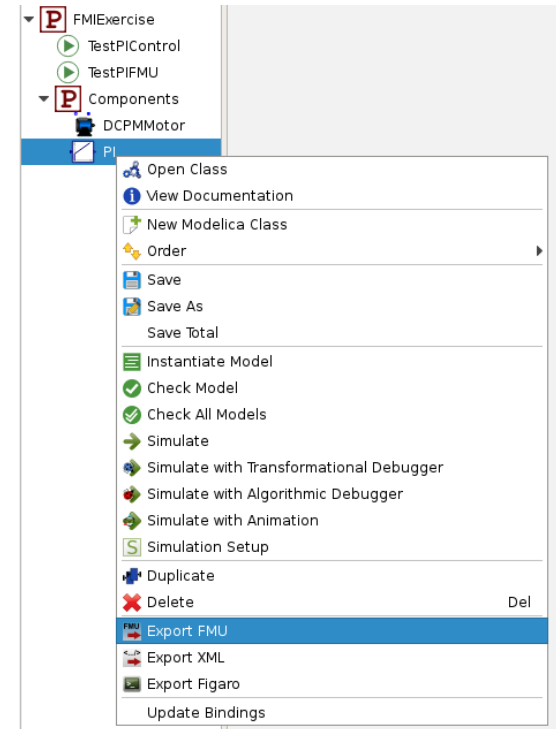
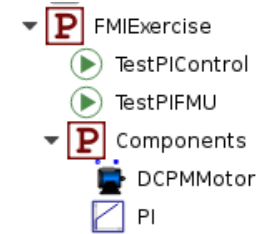
Exercise – FMU Export and Import (1)

- Open OMEdit and check FMI settings in Tools->Options



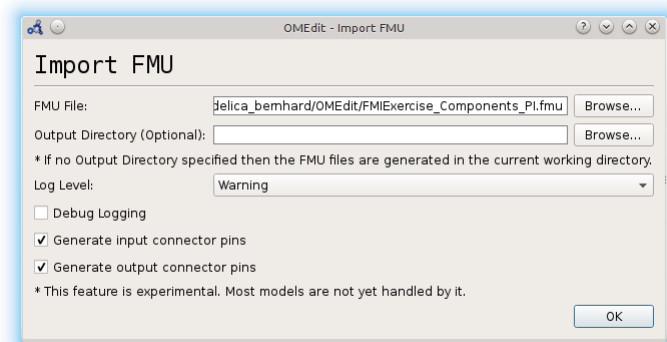
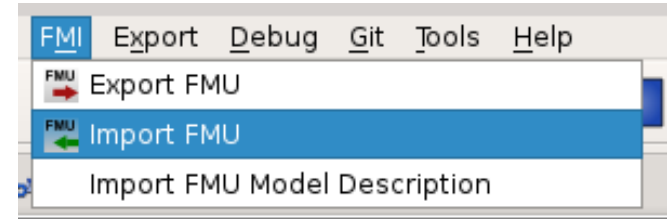
Exercise – FMU Export and Import (2)

- Find the `FMIEExercise.mo` file in the tutorial folder and open it in OMEdit. Click on the + at the left to open and see components `TestPIFMU`, `PI`, etc.
- **Goal:** (1) Export this `PI` block as FMU, (2) import the exported FMU, (3) compare simulation results of imported `PI` FMU block vs. native use of the `PI` block
- Export the `PI` block by selecting the model and use right-click context menu indicated at the right
- The message browser shows where the FMU was generated on your system



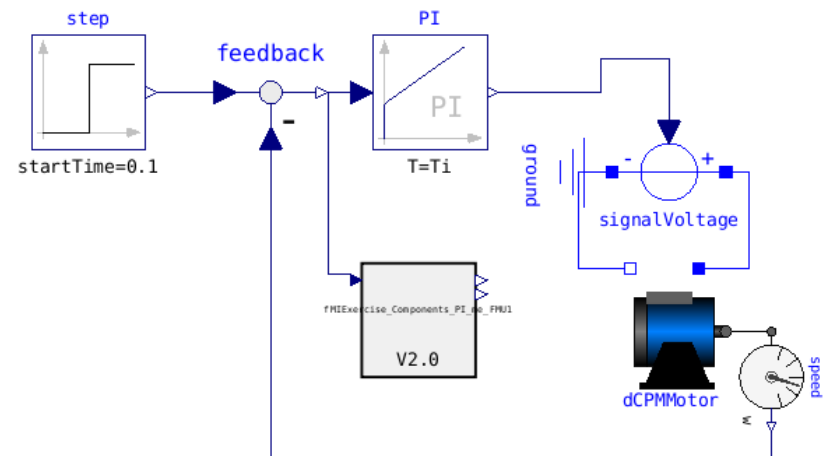
Exercise – FMU Export and Import (3)

- Import FMU by selecting FMI->Import FMU from the menu
- Find and select the FMU in the directory where it was exported before as indicated at the right
- The FMU should now appear in the package browser



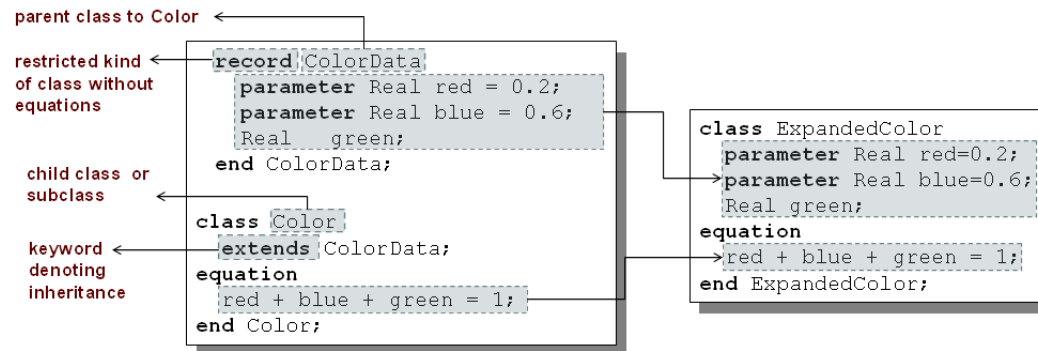
Exercise – FMU Export and Import (4)

- The imported FMU is wrapped inside a standard Modelica model and can be inserted by drag and drop into an existing model
- The model `TestPIFMU` has been prepared so that the results of the imported FMU can be easily compared to the native block. Simulate it and compare results by plotting



Part III

Modelica language concepts and textual modeling



Typed
Declarative
Equation-based
Textual Language

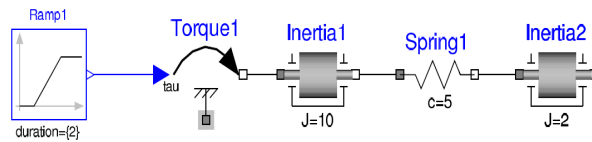
Hybrid
Modeling

Acausal Modeling

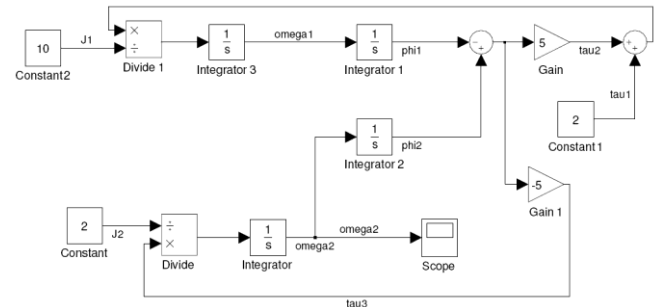
The order of computations is not decided at modeling time

Visual
Component
Level

Acausal



Causal



Equation
Level

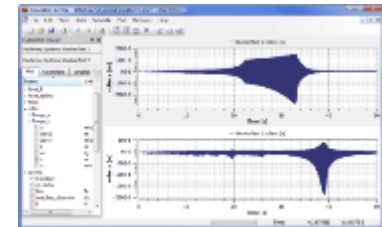
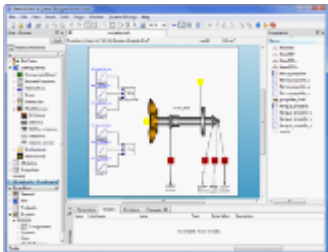
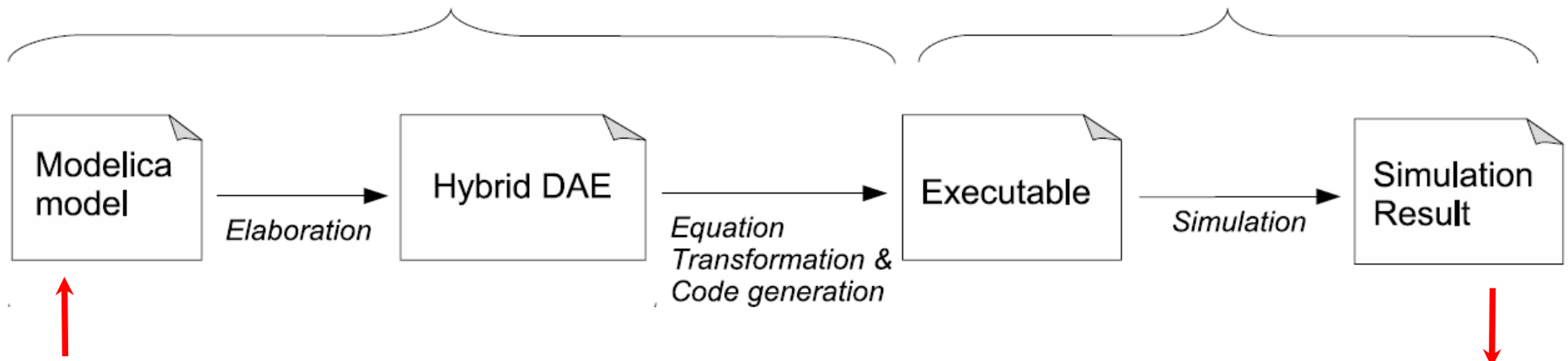
A resistor *equation*:
 $R \cdot i = v;$

Causal possibilities:
 $i := v/R;$
 $v := R \cdot i;$
 $R := v/i;$

Typical Simulation Process

“Static” semantics / compile time

“Dynamic” semantics / run time



Simple model - Hello World!

Equation: $x' = -x$

Initial condition: $x(0) = 1$

Continuous-time
variable

Parameter, constant
during simulation

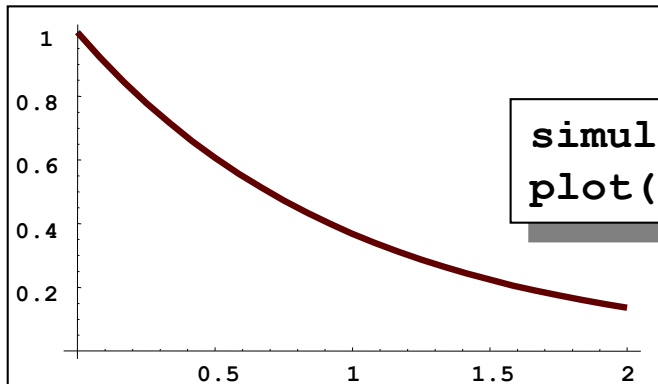
Name of model

Initial condition

```
model HelloWorld "A simple equation"  
  Real x(start=1);  
  parameter Real a = -1;  
  equation  
    der(x) = a*x;  
end HelloWorld;
```

Differential equation

Simulation in OpenModelica environment



```
simulate(HelloWorld, stopTime = 2)  
plot(x)
```

Modelica Variables and Constants

- Built-in primitive data types

Boolean **true** or **false**

Integer Integer value, e.g. **42** or **-3**

Real Floating point value, e.g. **2.4e-6**

String String, e.g. **"Hello world"**

Enumeration Enumeration literal e.g. **ShirtSize.Medium**

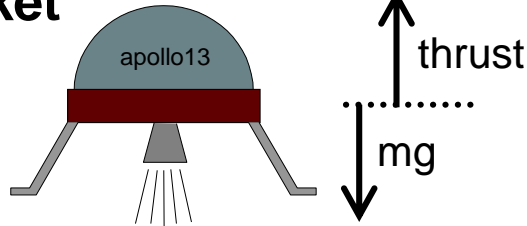
- Parameters are constant during simulation
- Two types of constants in Modelica

- **constant**
- **parameter**

```
constant Real      PI=3.141592653589793;  
constant String    redcolor = "red";  
constant Integer    one = 1;  
parameter Real      mass = 22.5;
```

A Simple Rocket Model

Rocket



$$acceleration = \frac{thrust - mass \cdot gravity}{mass}$$

$$mass' = -massLossRate \cdot abs(thrust)$$

$$altitude' = velocity$$

$$velocity' = acceleration$$

new model ←

parameters (changeable before the simulation) ←

floating point type ←

differentiation with regards to time ←

```

class Rocket; "rocket class"
  parameter String name;
  Real mass(start=1038.358);
  Real altitude(start= 59404);
  Real velocity(start= -2003);
  Real acceleration;
  Real thrust; // Thrust force on rocket
  Real gravity; // Gravity forcefield
  parameter Real massLossRate=0.000277;
equation
  (thrust-mass*gravity)/mass = acceleration;
  der(mass) = -massLossRate * abs(thrust);
  der(altitude) = velocity;
  der(velocity) = acceleration;
end Rocket;
  
```

→ declaration comment

→ start value

→ name + default value

→ mathematical equation (acausal)

Celestial Body Class

A class declaration creates a *type name* in Modelica

```
class CelestialBody
  constant Real    g = 6.672e-11;
  parameter Real   radius;
  parameter String name;
  parameter Real   mass;
end CelestialBody;
```

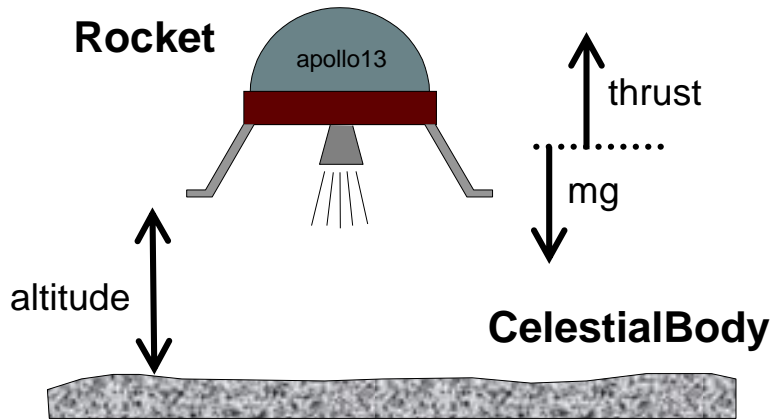


An *instance* of the class can be declared by *prefixing* the type name to a variable name

```
...
CelestialBody moon;
...
```

The declaration states that **moon** is a variable containing an object of type **CelestialBody**

Moon Landing



$$apollo.gravity = \frac{moon.g \cdot moon.mass}{(apollo.altitude + moon.radius)^2}$$

```

class MoonLanding
  parameter Real force1 = 36350;
  parameter Real force2 = 1308;
  protected
  parameter Real thrustEndTime = 210;
  parameter Real thrustDecreaseTime = 43.2;
  public
  Rocket apollo(name="apollo13");
  CelestialBody moon(name="moon", mass=7.382e22, radius=1.738e6);
equation
  apollo.thrust = if (time < thrustDecreaseTime) then force1
                  else if (time < thrustEndTime) then force2
                  else 0;
  apollo.gravity=moon.g*moon.mass/(apollo.altitude+moon.radius)^2;
end MoonLanding;

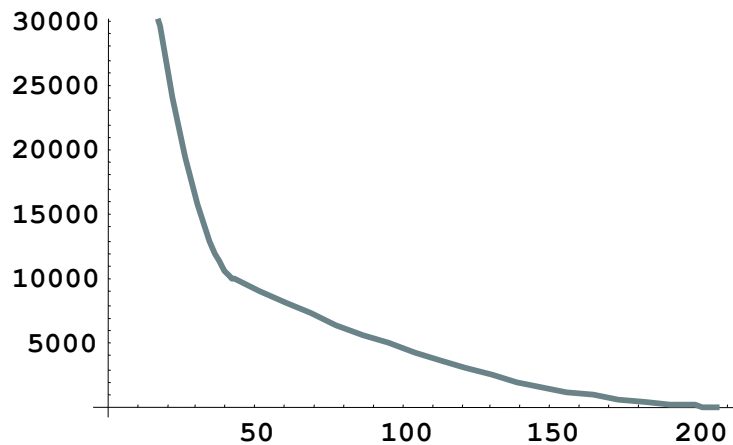
```

only access
inside the class

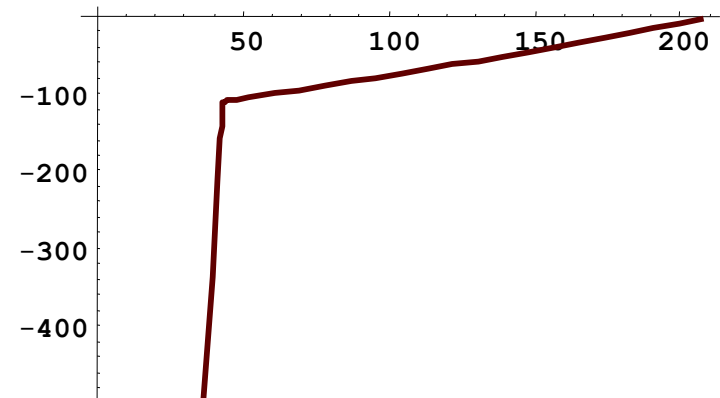
access by dot
notation outside
the class

Simulation of Moon Landing

```
simulate(MoonLanding, stopTime=230)  
plot(apollo.altitude, xrange={0,208})  
plot(apollo.velocity, xrange={0,208})
```



It starts at an altitude of 59404 (not shown in the diagram) at time zero, gradually reducing it until touchdown at the lunar surface when the altitude is zero



The rocket initially has a high negative velocity when approaching the lunar surface. This is reduced to zero at touchdown, giving a smooth landing

Specialized Class Keywords

- Classes can also be declared with other keywords, e.g.: `model`, `record`, `block`, `connector`, `function`, ...
- Classes declared with such keywords have specialized properties
- Restrictions and enhancements apply to contents of specialized classes
- After Modelica 3.0 the `class` keyword means the same as `model`
- Example: (Modelica 2.2). A `model` is a class that cannot be used as a connector class
- Example: A `record` is a class that only contains data, with no equations
- Example: A `block` is a class with fixed input-output causality

```
model CelestialBody
  constant Real    g = 6.672e-11;
  parameter Real   radius;
  parameter String name;
  parameter Real   mass;
end CelestialBody;
```

Modelica Functions

- Modelica Functions can be viewed as a specialized class with some restrictions and extensions
- A function can be called with arguments, and is instantiated dynamically when called

```
function sum
  input Real arg1;
  input Real arg2;
  output Real result;
algorithm
  result := arg1+arg2;
end sum;
```

Function Call – Example Function with for-loop

Example Modelica function call:

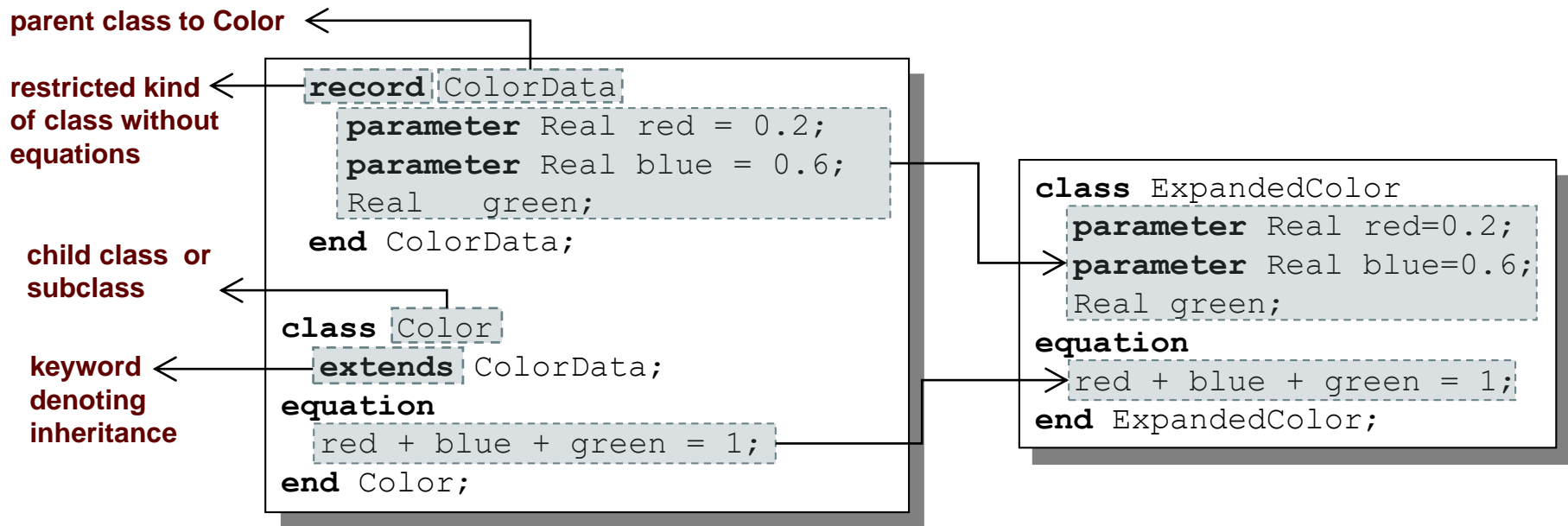
```
...  
p = polynomialEvaluator({1,2,3,4},21)
```

```
function PolynomialEvaluator  
  input Real A[:]; // array, size defined  
                // at function call time  
  input Real x := 1.0; // default value 1.0 for x  
  output Real sum;  
protected  
  Real xpower; // local variable xpower  
algorithm  
  sum := 0;  
  xpower := 1;  
  for i in 1:size(A,1) loop  
    sum := sum + A[i]*xpower;  
    xpower := xpower*x;  
  end for;  
end PolynomialEvaluator;
```

{1, 2, 3, 4} becomes the value of the coefficient vector A, and 21 becomes the value of the formal parameter x.

The function PolynomialEvaluator computes the value of a polynomial given two arguments: a coefficient vector A and a value of x.

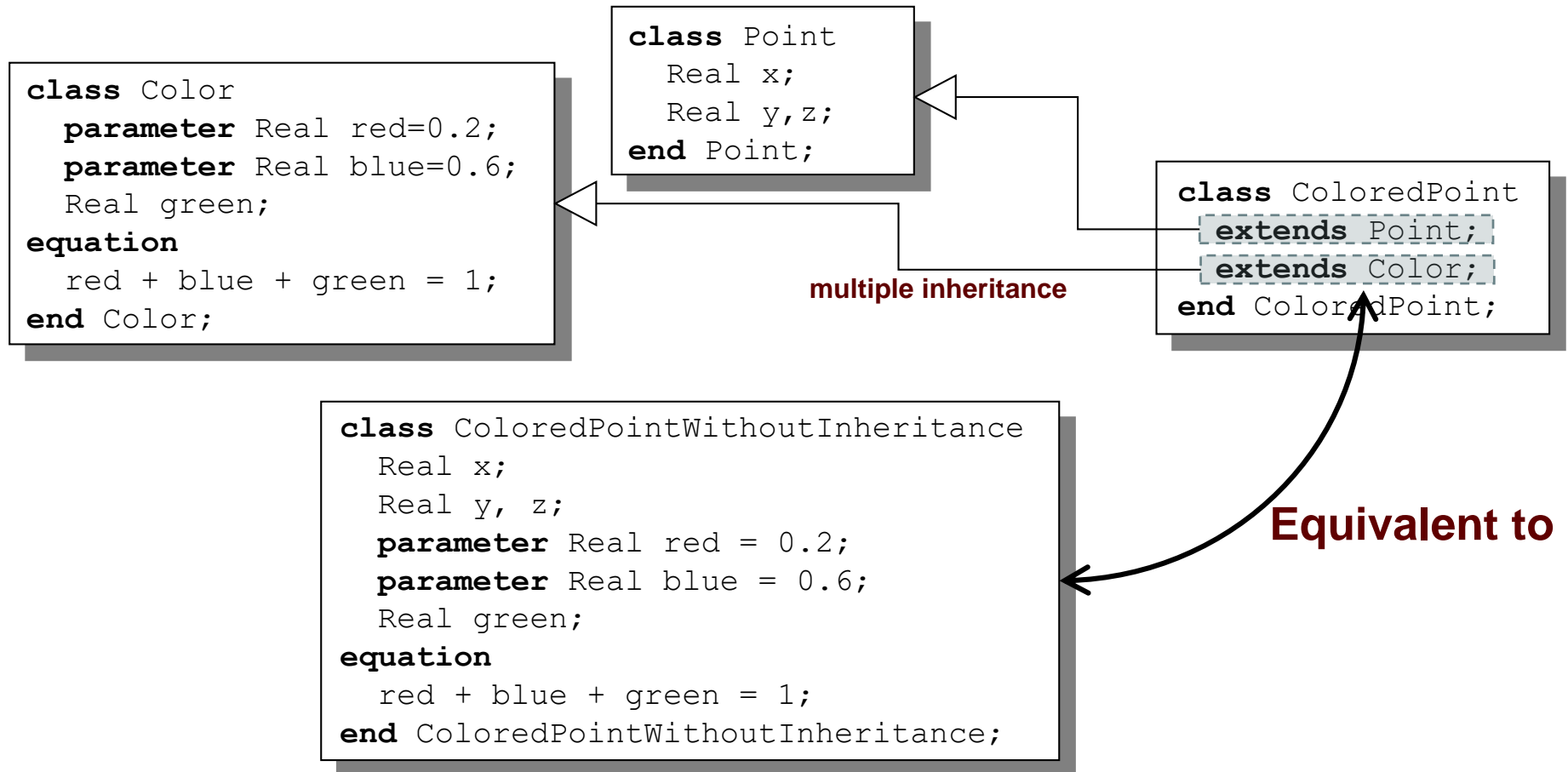
Inheritance



Data and behavior: field declarations, equations, and certain other contents are *copied* into the subclass

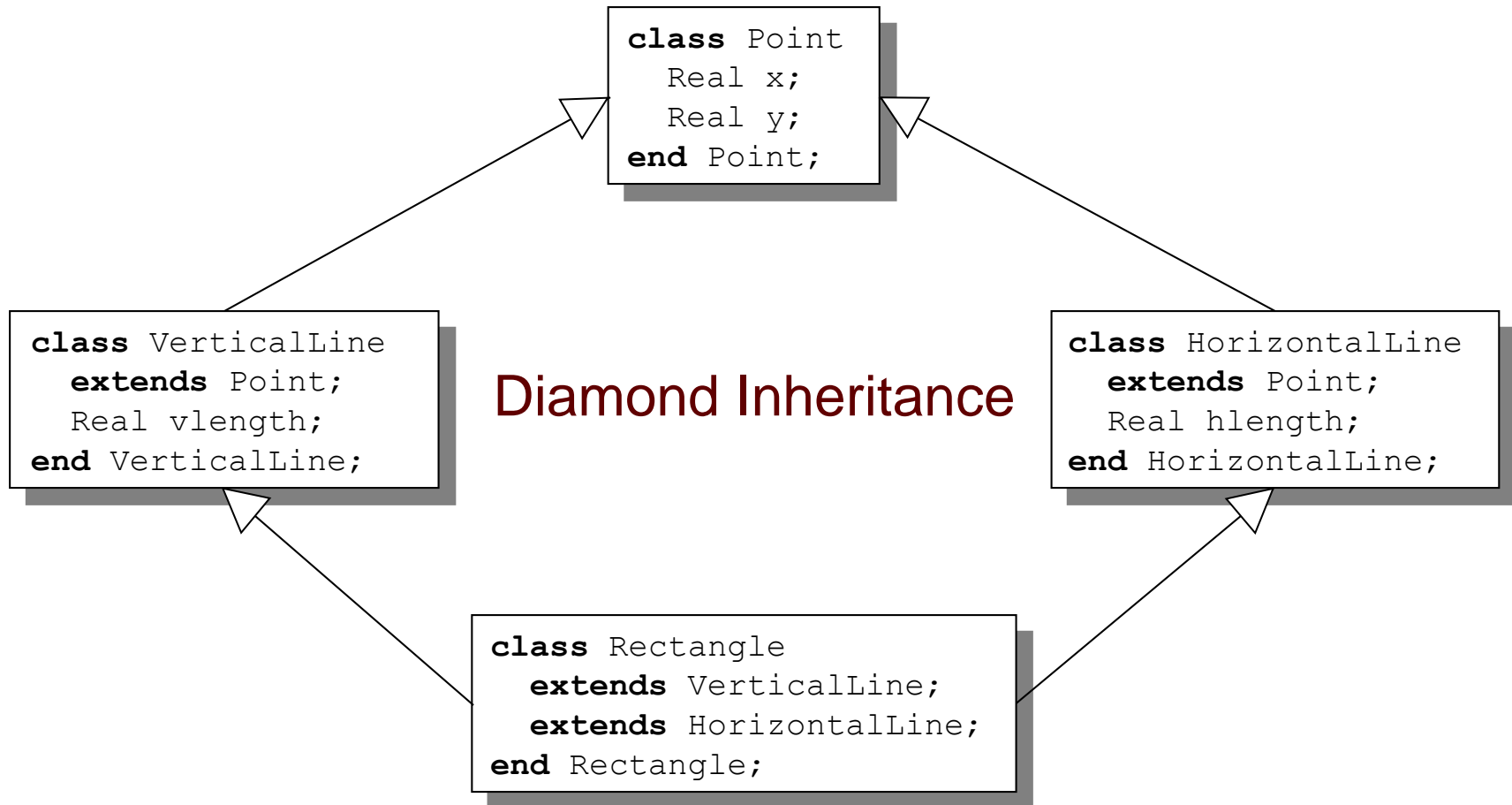
Multiple Inheritance

Multiple Inheritance is fine – inheriting both geometry and color



Multiple Inheritance cont'

Only one copy of multiply inherited class `Point` is kept



Simple Class Definition

- Simple Class Definition
 - Shorthand Case of Inheritance
- Example:

```
class SameColor = Color;
```

Equivalent to:

inheritance ←

```
class SameColor
  extends Color;
end SameColor;
```

- Often used for introducing new names of types:

```
type Resistor = Real;
```

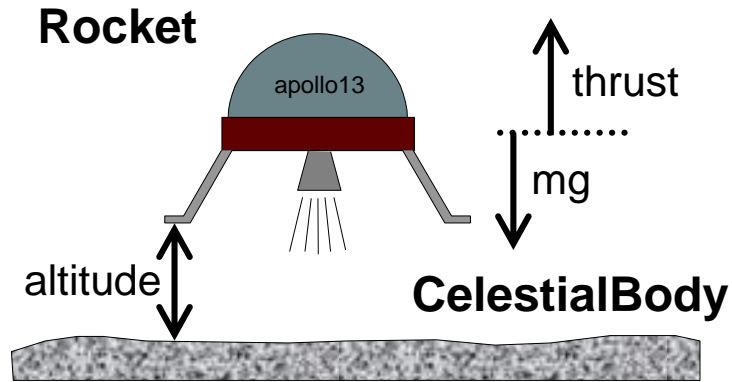
```
connector MyPin = Pin;
```


Inheritance Through Modification

- Modification is a concise way of combining inheritance with declaration of classes or instances
- A *modifier* modifies a declaration equation in the inherited class
- Example: The class `Real` is inherited, modified with a different `start` value equation, and instantiated as an altitude variable:

```
...  
Real altitude(start= 59404);  
...
```

The Moon Landing - Example Using Inheritance (I)



```

model Body "generic body"
  Real mass;
  String name;
end Body;
  
```

```

model CelestialBody
  extends Body;
  constant Real g = 6.672e-11;
  parameter Real radius;
end CelestialBody;
  
```

```

model Rocket "generic rocket class"
  extends Body;
  parameter Real massLossRate=0.000277;
  Real altitude(start= 59404);
  Real velocity(start= -2003);
  Real acceleration;
  Real thrust;
  Real gravity;
equation
  thrust-mass*gravity= mass*acceleration;
  der(mass)= -massLossRate*abs(thrust);
  der(altitude)= velocity;
  der(velocity)= acceleration;
end Rocket;
  
```

The Moon Landing - Example using Inheritance (II)

```

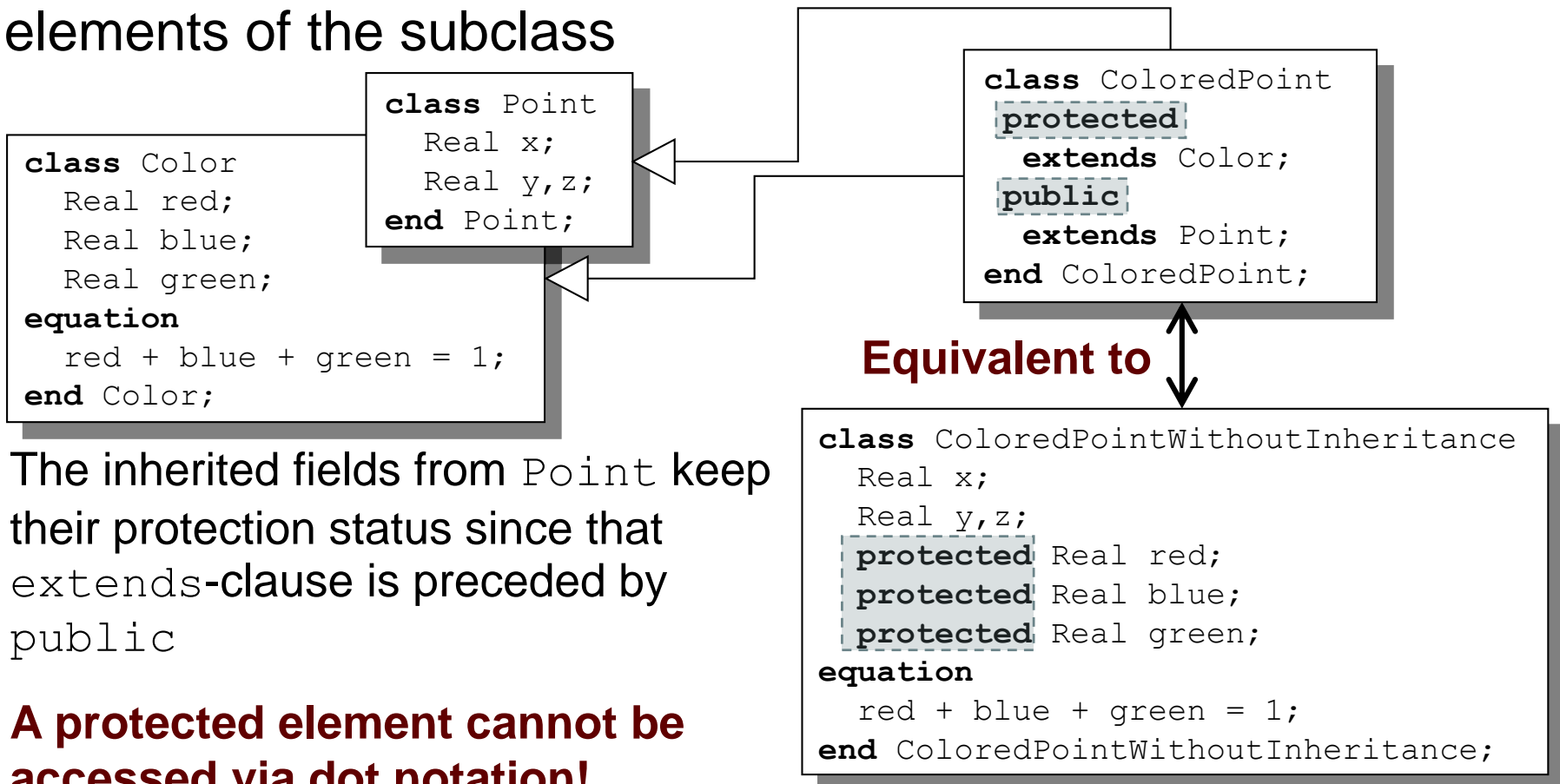
model MoonLanding
  parameter Real force1 = 36350;
  parameter Real force2 = 1308;
  parameter Real thrustEndTime = 210;
  parameter Real thrustDecreaseTime = 43.2;
  Rocket      apollo (name="apollo13", mass(start=1038.358) );
  CelestialBody moon (mass=7.382e22, radius=1.738e6, name="moon");
equation
  apollo.thrust = if (time<thrustDecreaseTime) then force1
                  else if (time<thrustEndTime) then force2
                  else 0;
  apollo.gravity =moon.g*moon.mass/(apollo.altitude+moon.radius)^2;
end Landing;

```

inherited
parameters

Inheritance of Protected Elements

If an `extends`-clause is preceded by the `protected` keyword, all inherited elements from the superclass become protected elements of the subclass



Exercises Part III a (15 minutes)

Exercises Part III a

- Start OMNotebook (part of OpenModelica)
 - **Start**->Programs->OpenModelica->OMNotebook
 - **Open File**: Exercises-ModelicaTutorial.onb from the directory you copied your tutorial files to.
 - **Note**: The DrModelica electronic book has been automatically opened when you started OMNotebook.
 - **(Alternatively)**: Open the OMWeb notebook
<http://omwebbook.openmodelica.org/>
- Open Exercises-ModelicaTutorial.pdf (also available in printed handouts)

Exercises 2.1 and 2.2 (See also next two pages)

- Open the **Exercises-ModelicaTutorial.onb** found in the Tutorial directory you copied at installation.
- **Exercise 2.1.** Simulate and plot the HelloWorld example. Do a slight change in the model, re-simulate and re-plot. Try command-completion, `val()`, etc.

```
class HelloWorld "A simple equation"  
  Real x(start=1);  
equation  
  der(x) = -x;  
end HelloWorld;
```

```
simulate(HelloWorld, stopTime = 2)  
plot(x)
```

- Locate the VanDerPol model in DrModelica (link from Section 2.1), using OMNotebook!
- **(extra) Exercise 2.2:** Simulate and plot VanDerPol. Do a slight change in the model, re-simulate and re-plot.

Exercise 2.1 – Hello World!

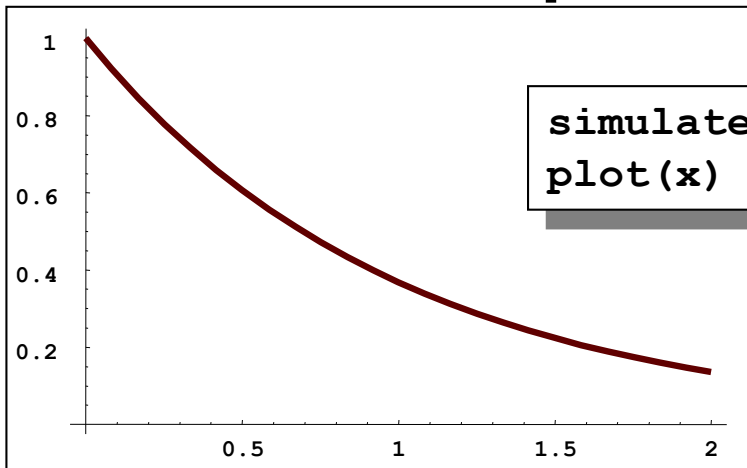
A Modelica “Hello World” model

Equation: $x' = -x$

Initial condition: $x(0) = 1$

```
class HelloWorld "A simple equation"  
  parameter Real a=-1;  
  Real x(start=1);  
equation  
  der(x) = a*x; (*xxxxxx s*)  
end HelloWorld;
```

Simulation in OpenModelica environment

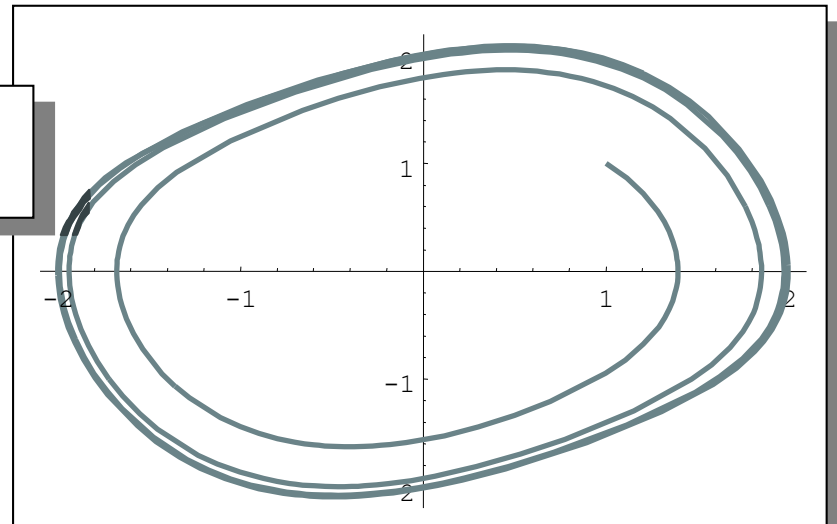


```
simulate(HelloWorld, stopTime = 2)  
plot(x)
```


(extra) Exercise 2.2 – Van der Pol Oscillator

```
class VanDerPol "Van der Pol oscillator model"  
  Real x(start = 1) "Descriptive string for x"; // x starts at 1  
  Real y(start = 1) "y coordinate";           // y starts at 1  
  parameter Real lambda = 0.3;  
equation  
  der(x) = y;                               // This is the 1st diff equation //  
  der(y) = -x + lambda*(1 - x*x)*y; /* This is the 2nd diff equation */  
end VanDerPol;
```

```
simulate(VanDerPol, stopTime = 25)  
plotParametric(x, y)
```



(extra) Exercise 2.3 – DAE Example

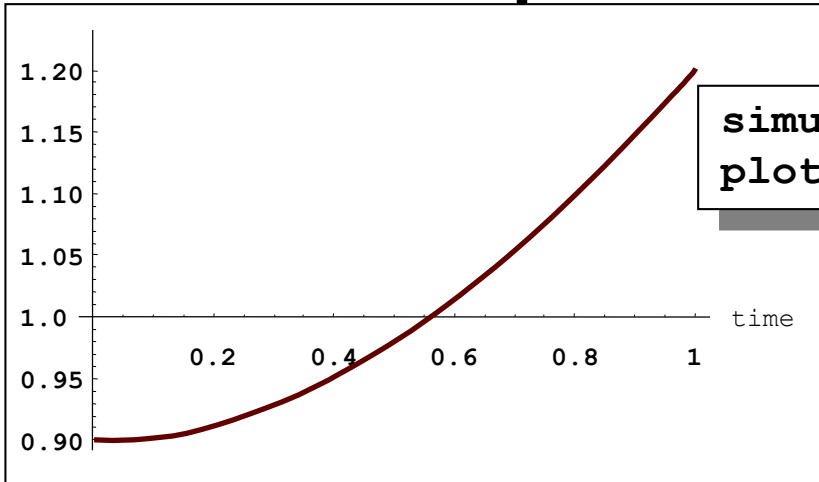
Include algebraic equation

Algebraic equations contain
no derivatives

Exercise: Locate in DrModelica.
Simulate and plot. Change
the model, simulate+plot.

```
class DAEexample
  Real x(start=0.9);
  Real y;
equation
  der(y) + (1 + 0.5 * sin(y)) * der(x)
    = sin(time);
  x - y = exp(-0.9 * x) * cos(y);
end DAEexample;
```

Simulation in OpenModelica environment



```
simulate(DAEexample, stopTime = 1)
plot(x)
```

Exercise 2.4 – Model the system below

- Model this Simple System of Equations in Modelica

$$\dot{x} = 2 * x * y - 3 * x$$

$$\dot{y} = 5 * y - 7 * x * y$$

$$x(0) = 2$$

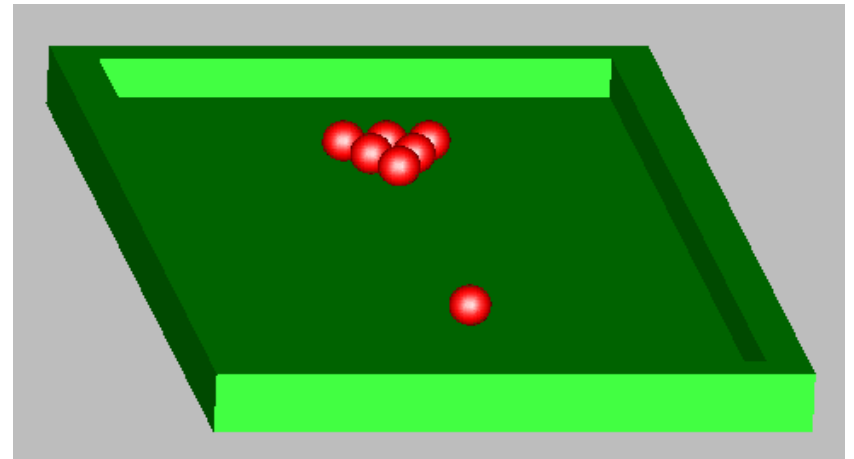
$$y(0) = 3$$

(extra) Exercise 2.5 – Functions

- a) Write a function, **sum2**, which calculates the sum of Real numbers, for a vector of arbitrary size.
- b) Write a function, **average**, which calculates the average of Real numbers, in a vector of arbitrary size. The function **average** should make use of a function call to **sum2**.

Part III b

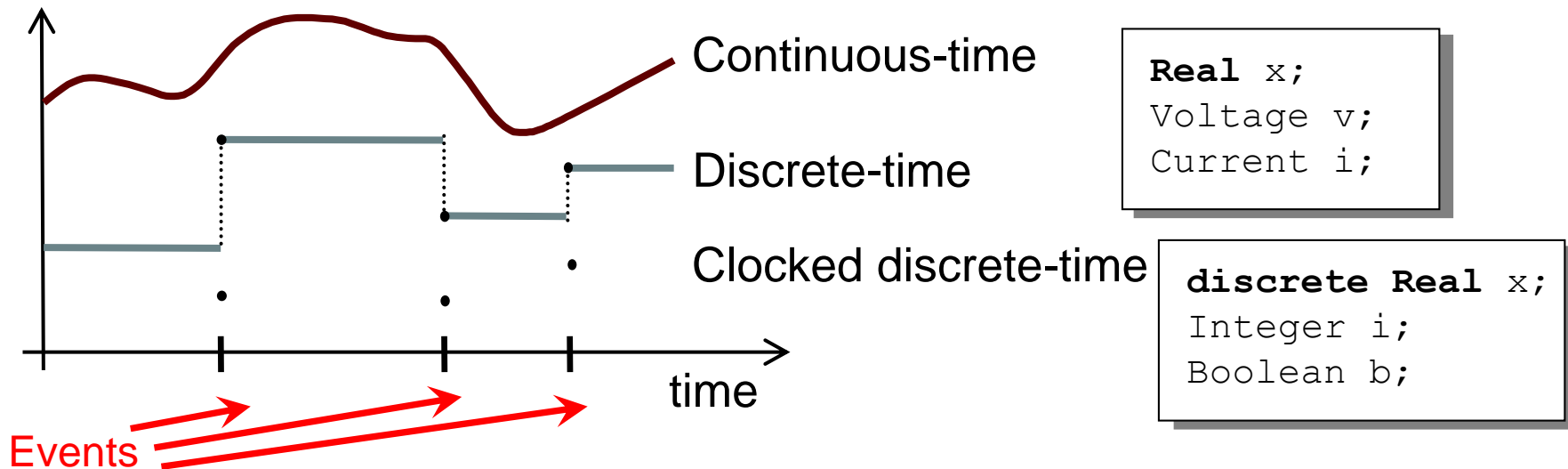
Discrete Events and Hybrid Systems



Picture: Courtesy Hilding Elmqvist

Modelica Hybrid Modeling

Hybrid modeling = continuous-time + discrete-time modeling



- A *point* in time that is instantaneous, i.e., has zero duration
- An event *condition* or *clock tick* so that the event can take place
- A set of *variables* that are associated with the event
- Some *behavior* associated with the event, e.g. *conditional equations* that become active or are deactivated at the event

Event Creation – if

if-equations, if-statements, and if-expressions

```
if <condition> then
  <equations>
elseif <condition> then
  <equations>
else
  <equations>
end if;
```

```
model Diode "Ideal diode"
  extends TwoPin;
  Real s;
  Boolean off;
  equation
    off = s < 0;
  if off then
    v=s
  else
    v=0;
  end if;
  i = if off then 0 else s;
end Diode;
```

false if $s < 0$

If-equation choosing
equation for v

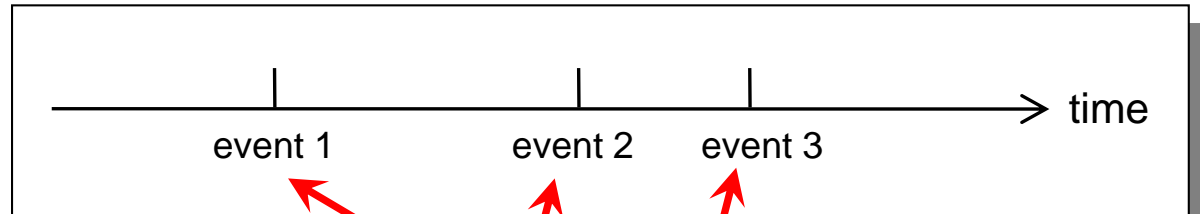
If-expression

Event Creation – when

when-equations (two kinds: unclocked and clocked)

```
when <conditions> then  
  <equations>  
end when; // un-clocked version
```

```
when clock then  
  <equations>  
end when; // clocked version
```



Equations only active at event times

Time event

```
when time >= 10.0 then  
  ...  
end when;
```

Only dependent on time, can be scheduled in advance

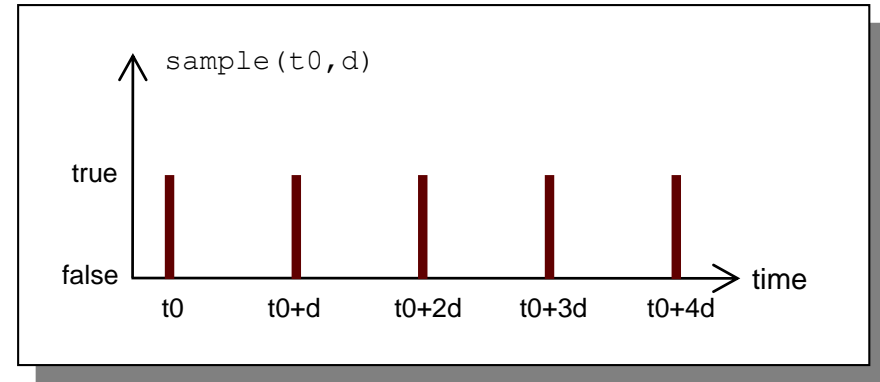
State event

```
when sin(x) > 0.5 then  
  ...  
end when;
```

Related to a state. Check for zero-crossing

Generating Repeated Events by unclocked sample

The call `sample(t0, d)` returns true and triggers events at times $t_0 + i \cdot d$, where $i = 0, 1, \dots$

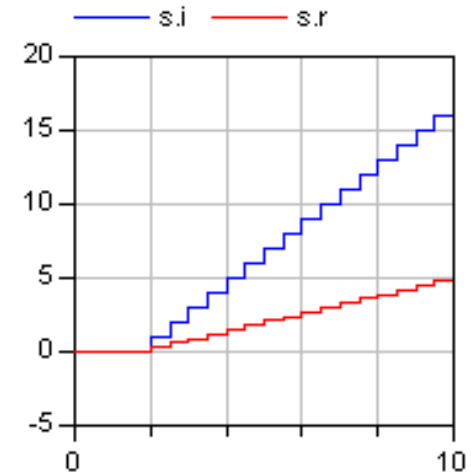


Variables need to be discrete

```
model SamplingClock
  Integer i;
  discrete Real r;
equation
  when sample(2, 0.5) then
    i = pre(i) + 1;
    r = pre(r) + 0.3;
  end when;
end SamplingClock;
```

Creates an event after 2 s, then each 0.5 s

`pre(...)` takes the previous value before the event.



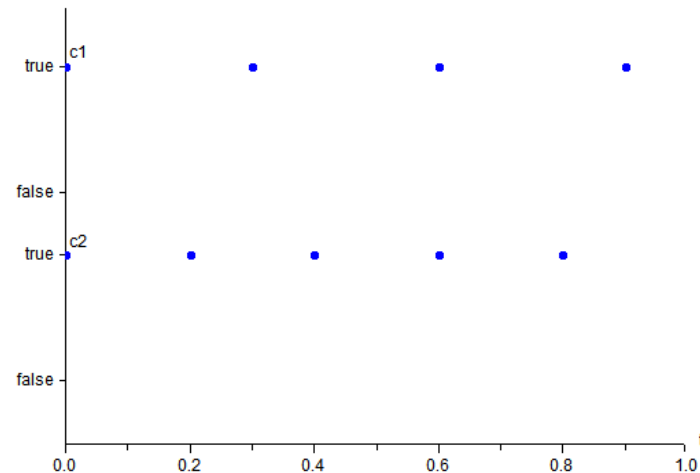
Generating Clock Tick Events using Clock()

(clocked models, Modelica 3.3)

- Clock() – inferred clock
- Clock(intervalCounter, resolution) – clock with Integer quotient (rational number) interval
- Clock(interval) – clock with a Real value interval
- Clock(condition, startInterval)
- Clock – solver clock

class ClockTicks

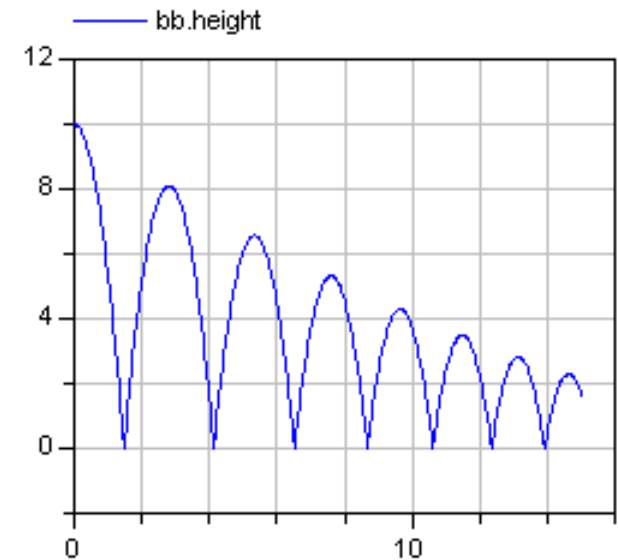
```
// Integer quotient rational number interval clock  
Clock c1 = Clock(3,10); // ticks: 0, 3/10, 6/10, ..  
// Clock with real value interval between ticks  
Clock c2 = Clock(0.2); // ticks: 0.0, 0.2, 0.4, ...  
end ClockTicks;
```



Reinit - Discontinuous Changes

The value of a *continuous-time* state variable can be instantaneously changed by a `reinit`-equation within a `when`-equation

```
model BouncingBall "the bouncing ball model"
  parameter Real g=9.81; //gravitational acc.
  parameter Real c=0.90; //elasticity constant
  Real height(start=10), velocity(start=0);
equation
  der(height) = velocity;
  der(velocity)=-g;
  when height<0 then
    reinit(velocity, -c*velocity);
  end when;
end BouncingBall;
```

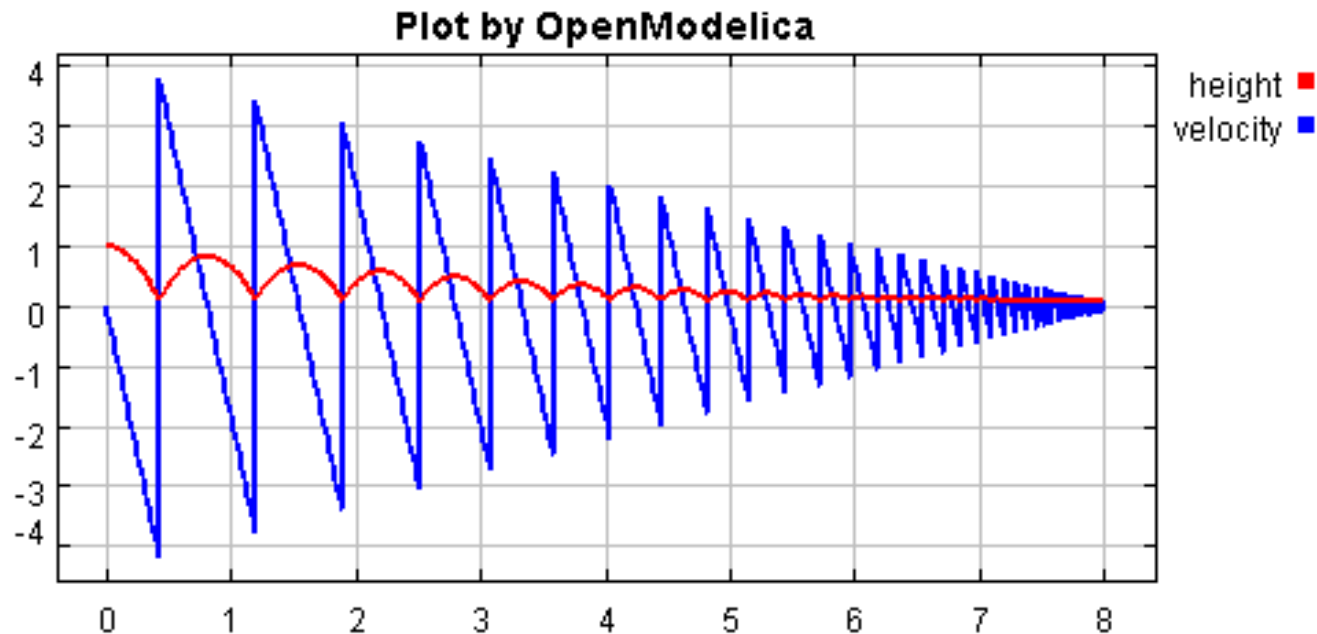


Initial conditions

Reinit "assigns"
continuous-time variable
`velocity` a new value

Exercise 2.6 – BouncingBall

- Locate the BouncingBall model in one of the hybrid modeling sections of DrModelica (the When-Equations link in Section 2.9), run it, change it slightly, and re-run it.



Part IIIc

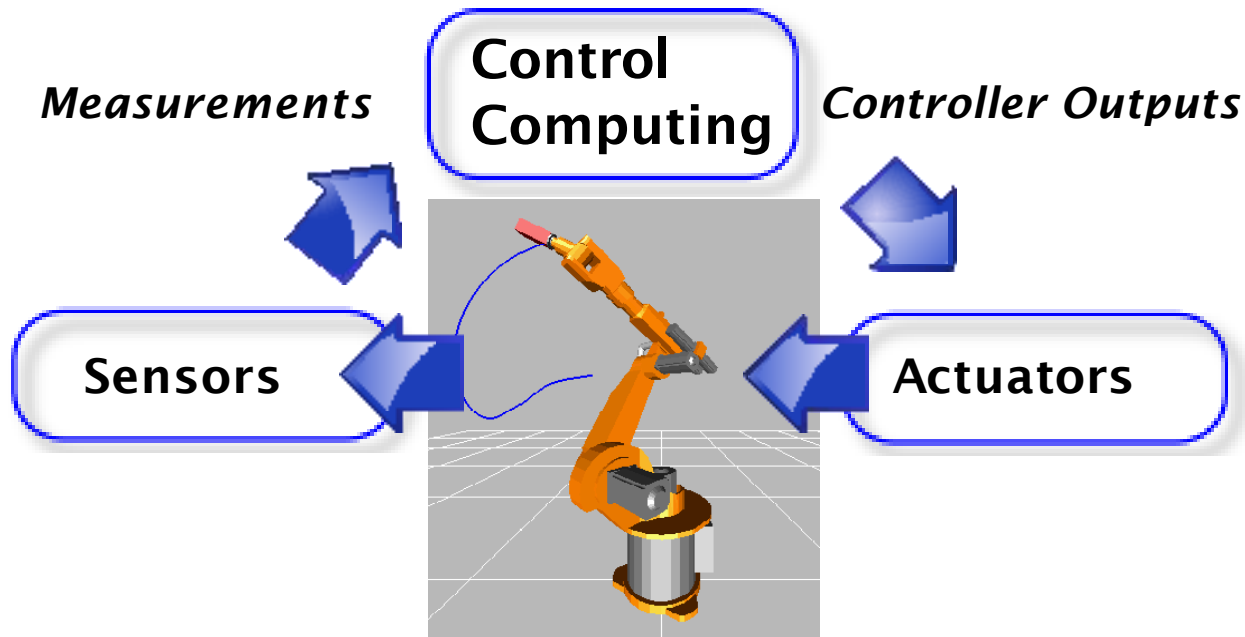
Clocked Synchronous Models and State Machines

and Applications for Digital Controllers

Control System Applications

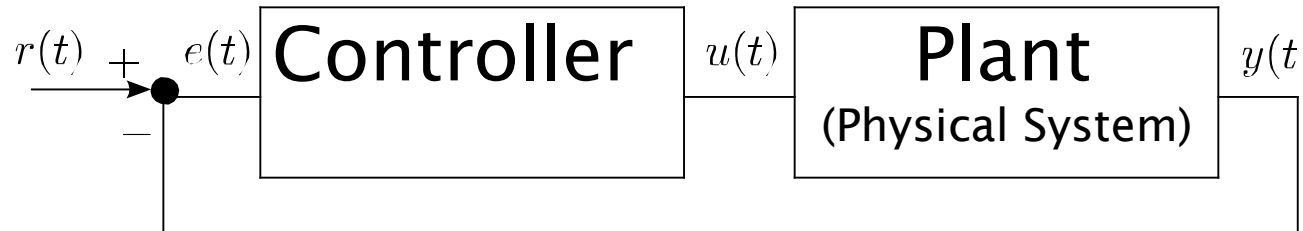
Control System

A control system is a device, or set of devices, that manages, commands, directs or regulates the behavior of other devices or systems (wikipedia).



Control Theory Perspective

Feedback Control System



$r(t)$ reference (setpoint)

$e(t)$ error

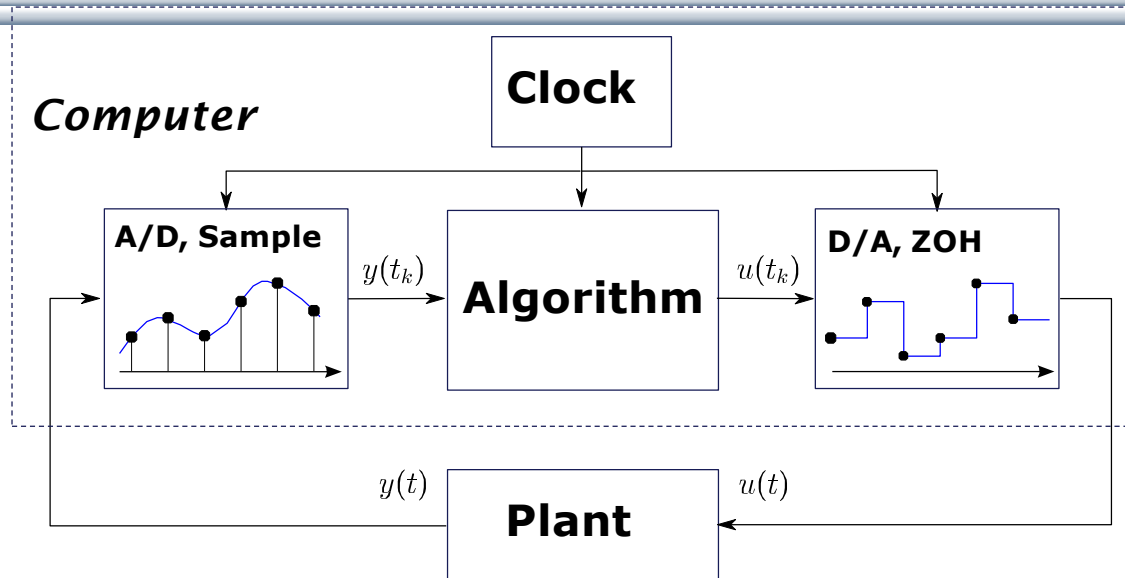
$y(t)$ measured process variable (plant output)

$u(t)$ control output variable (plant input)

Usual Objective

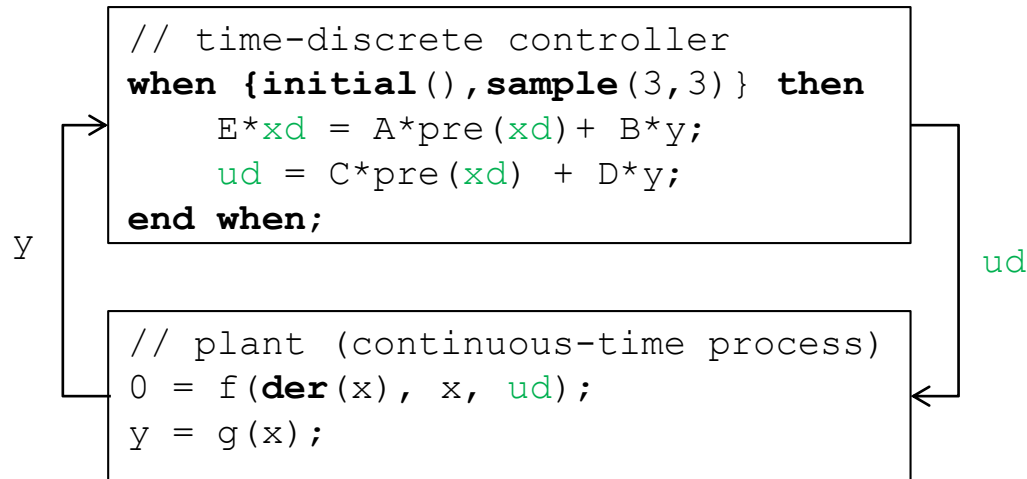
Plant output should follow the reference signal.

Embedded Real-Time Control System



1. **Discrete-time** controller + **continuous-time** plant \equiv *hybrid system* or *sampled-data system*
2. Interface between digital and analog world: Analog to Digital and Digital to Analog Converters (ADC and DAC).
3. ADC \rightarrow Algorithm \rightarrow DAC is synchronous (zero-delay model!)
4. A *clock* controls the *sampling instants*. Usually *periodic sampling*.

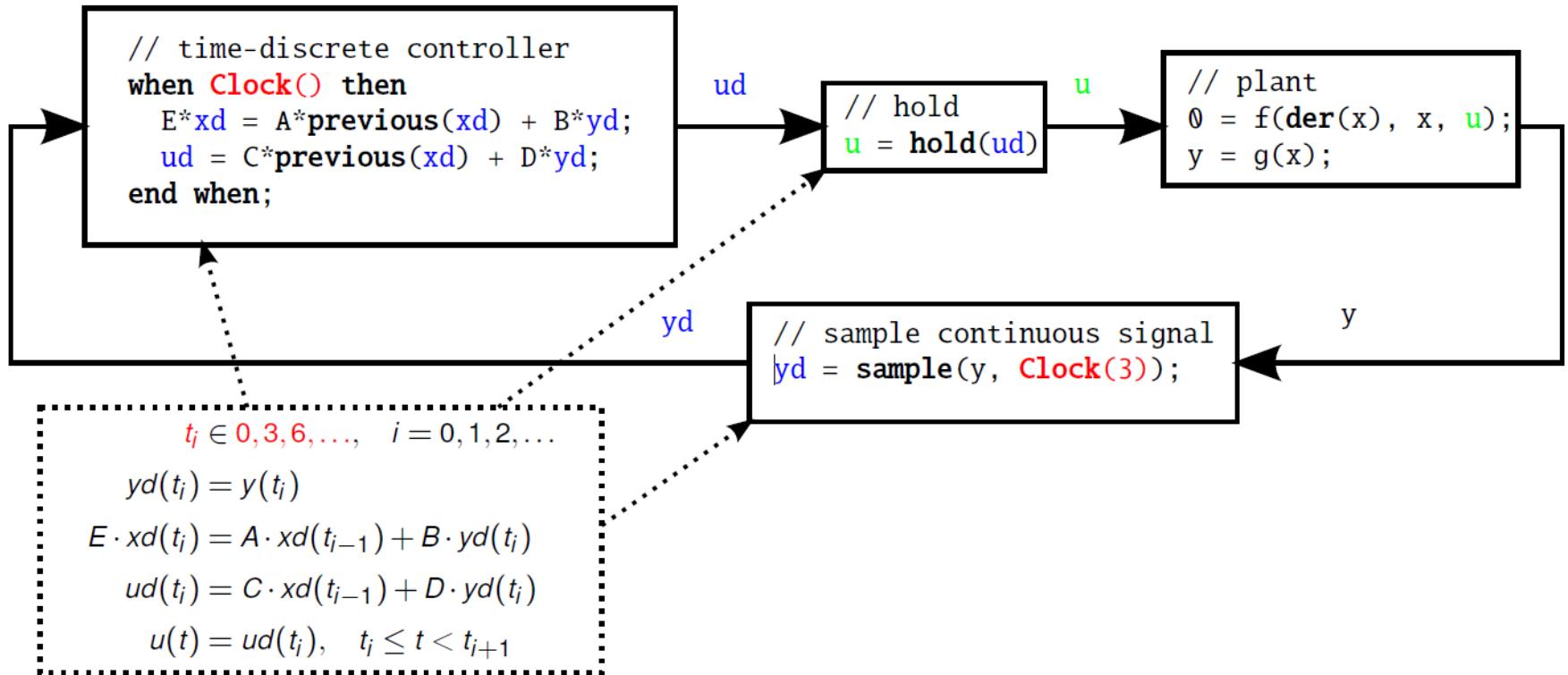
Controller with Sampled Data-Systems (unlocked models, using pre() and sample())



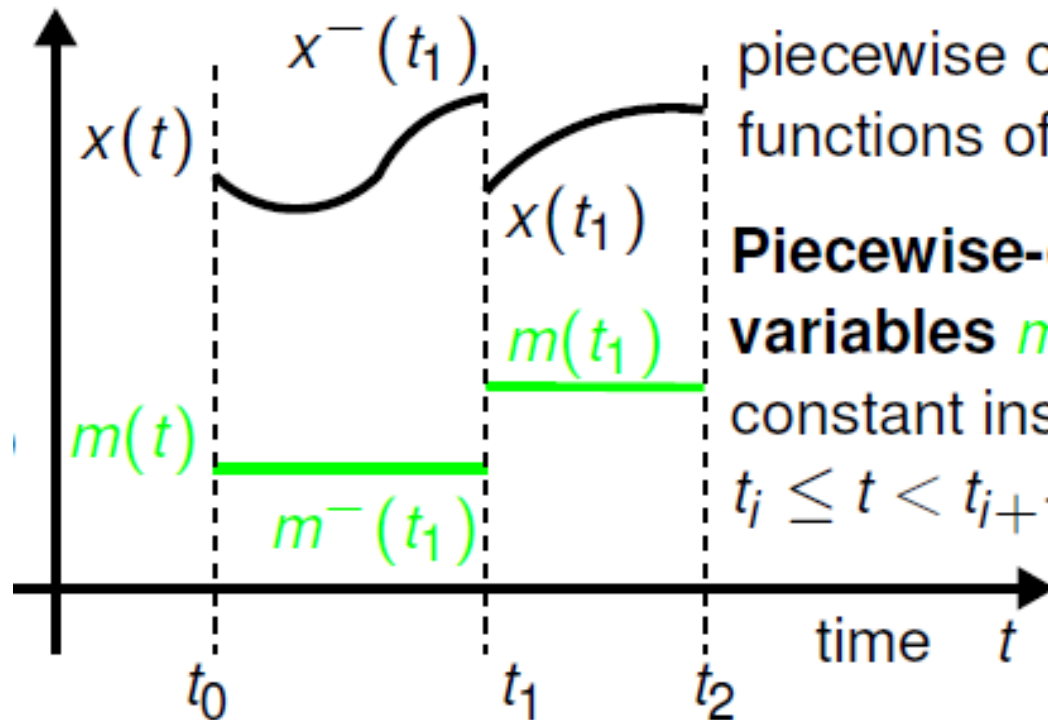
- y is automatically sampled at $t = 3, 6, 9, \dots$;
- xd , u are piecewise-constant variables that change values at sampling events (implicit zero-order hold)
- `initial()` triggers event at initialization ($t=0$)

Controller with Clocked Synchronous Constructs

clocked models using `Clock()`, `previous()`, `hold()` in Modelica 3.3



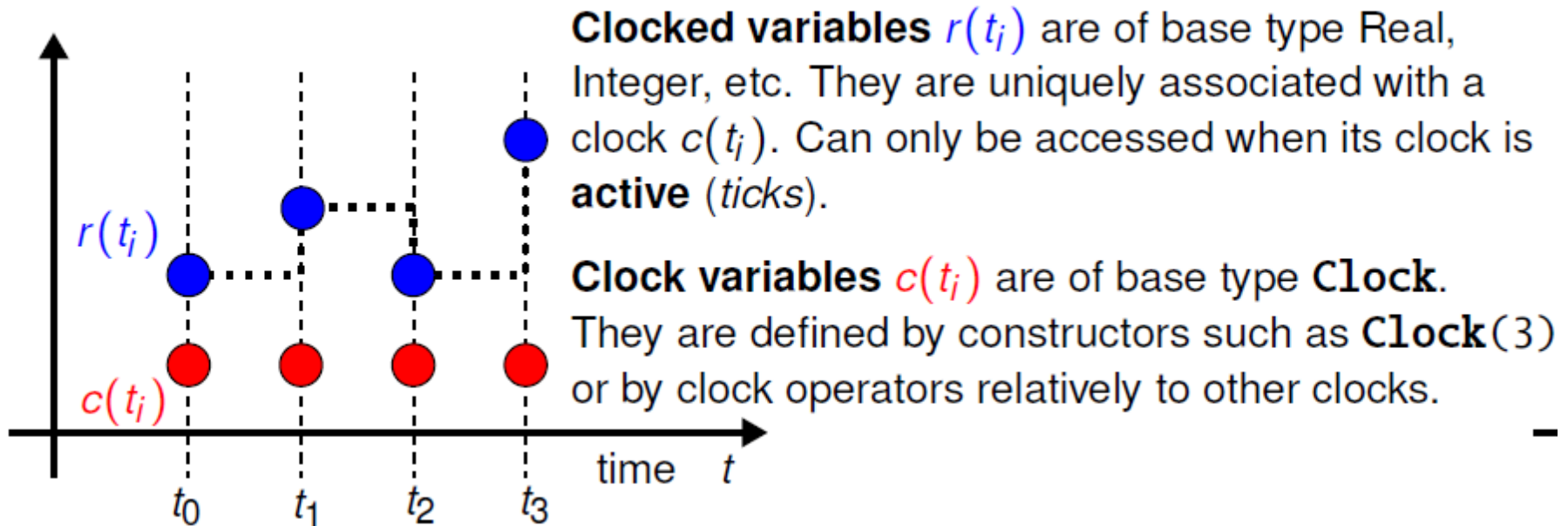
Unlocked Variables in Modelica 3.2



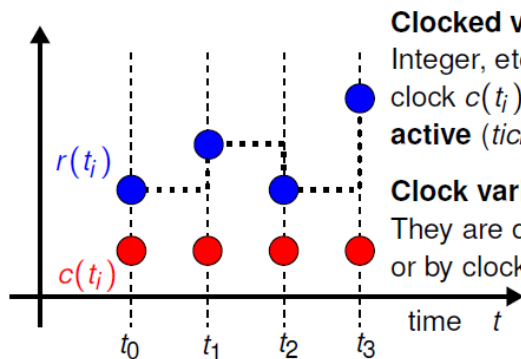
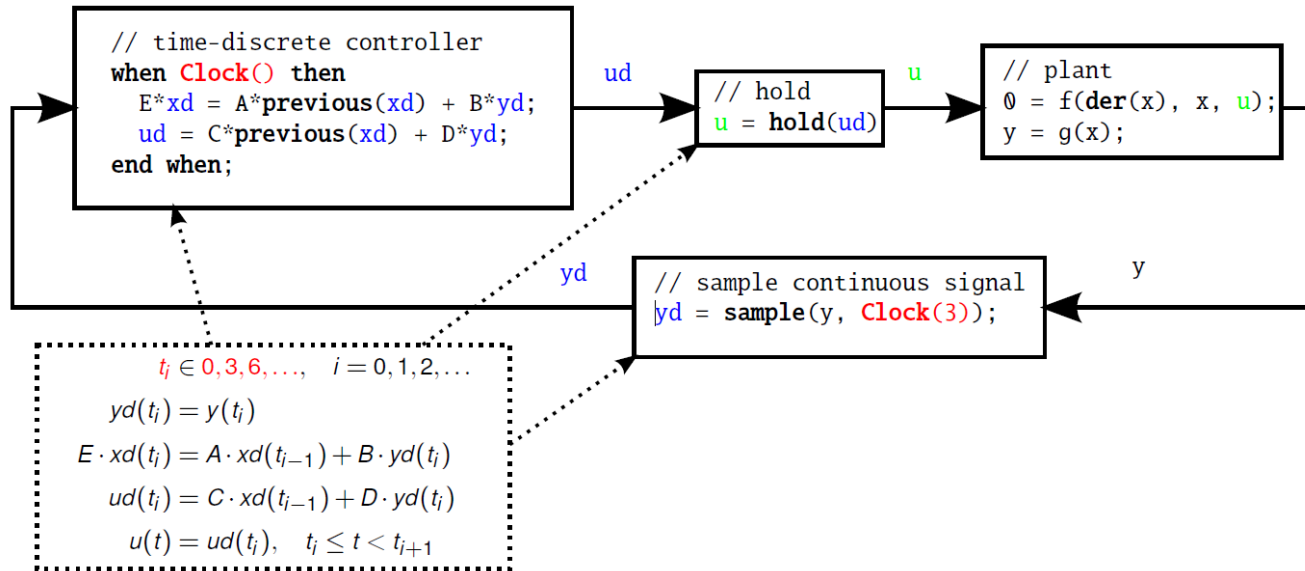
Continuous variables are Real numbers defined as piecewise continuous functions of time.

Piecewise-constant variables $m(t)$ are constant inside each $t_j \leq t < t_{j+1}$.

Clock variables (Clock) and Clocked Variables (Real) (in Modelica 3.3)

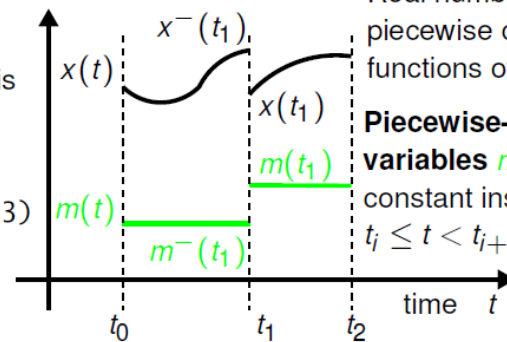


Clocked Synchronous Extension in Modelica 3.3



Clocked variables $r(t_i)$ are of base type Real, Integer, etc. They are uniquely associated with a clock $c(t_i)$. Can only be accessed when its clock is **active** (ticks).

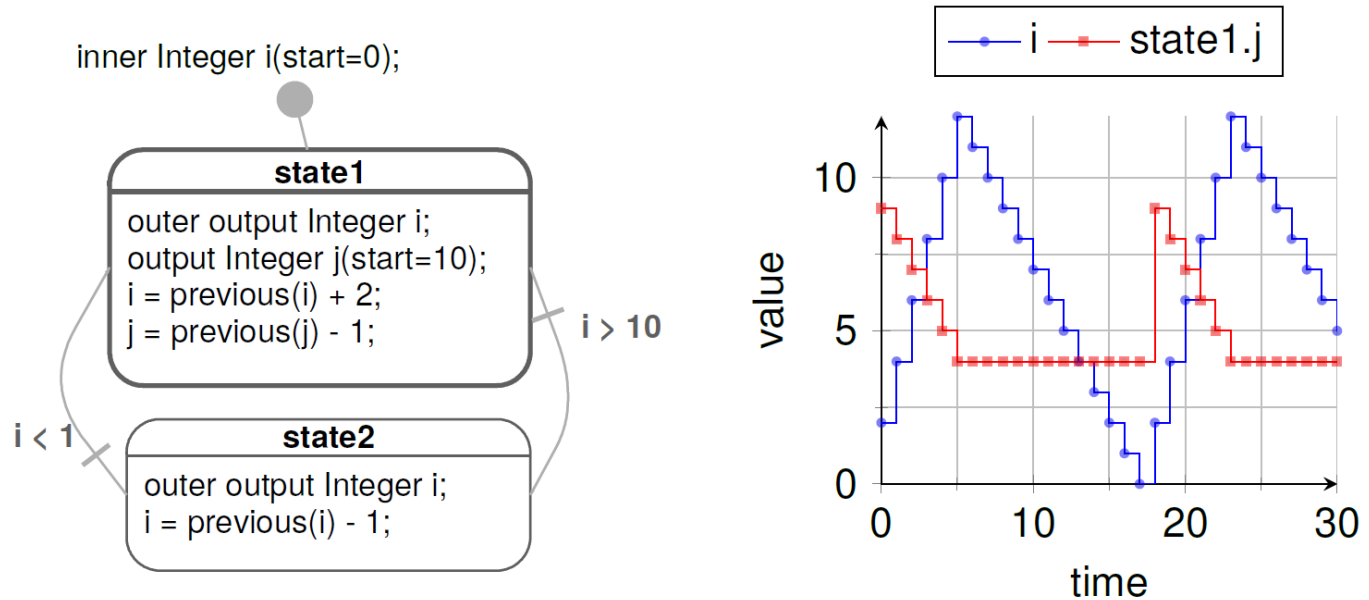
Clock variables $c(t_i)$ are of base type **Clock**. They are defined by constructors such as **Clock(3)** or by clock operators relatively to other clocks.



Continuous variables are Real numbers defined as piecewise continuous functions of time.

Piecewise-constant variables $m(t)$ are constant inside each $t_i \leq t < t_{i+1}$.

State Machines in Modelica 3.3: Simple Example

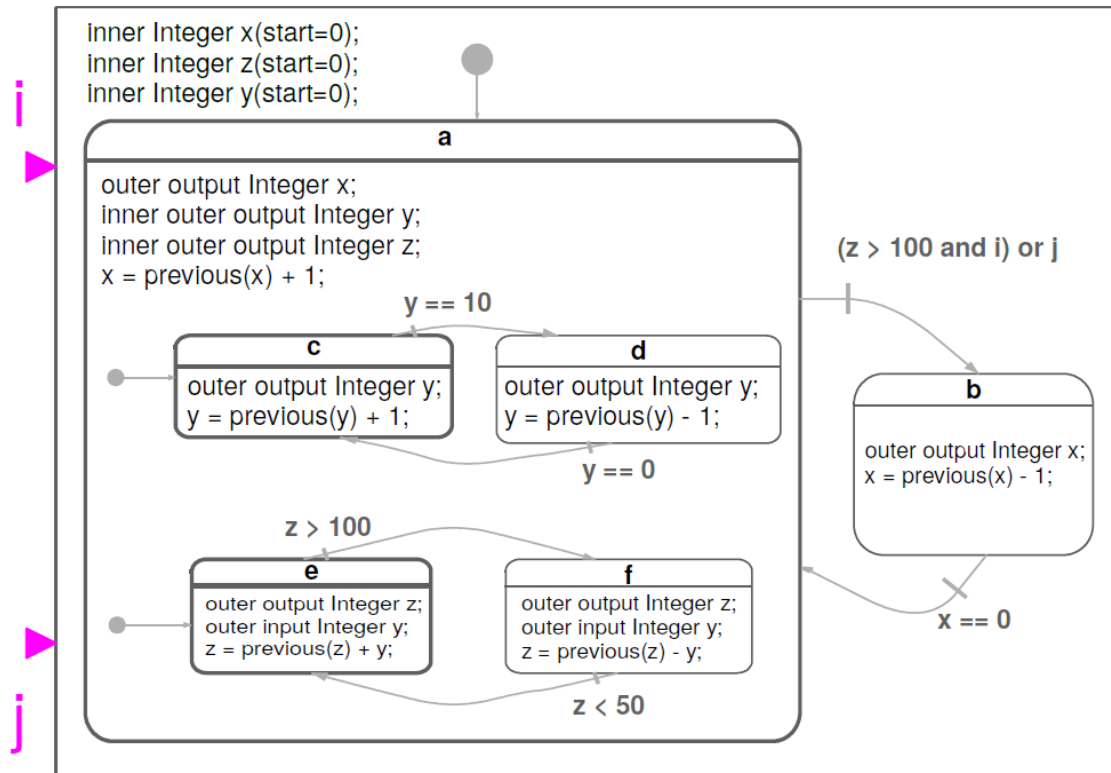


- Equations are active if corresponding *clock* ticks. Defaults to periodic clock with 1.0 s sampling period
- “i” is a shared variable, “j” is a local variable. Transitions are “*delayed*” and enter states by “*reset*”

Simple Example: Modelica Code

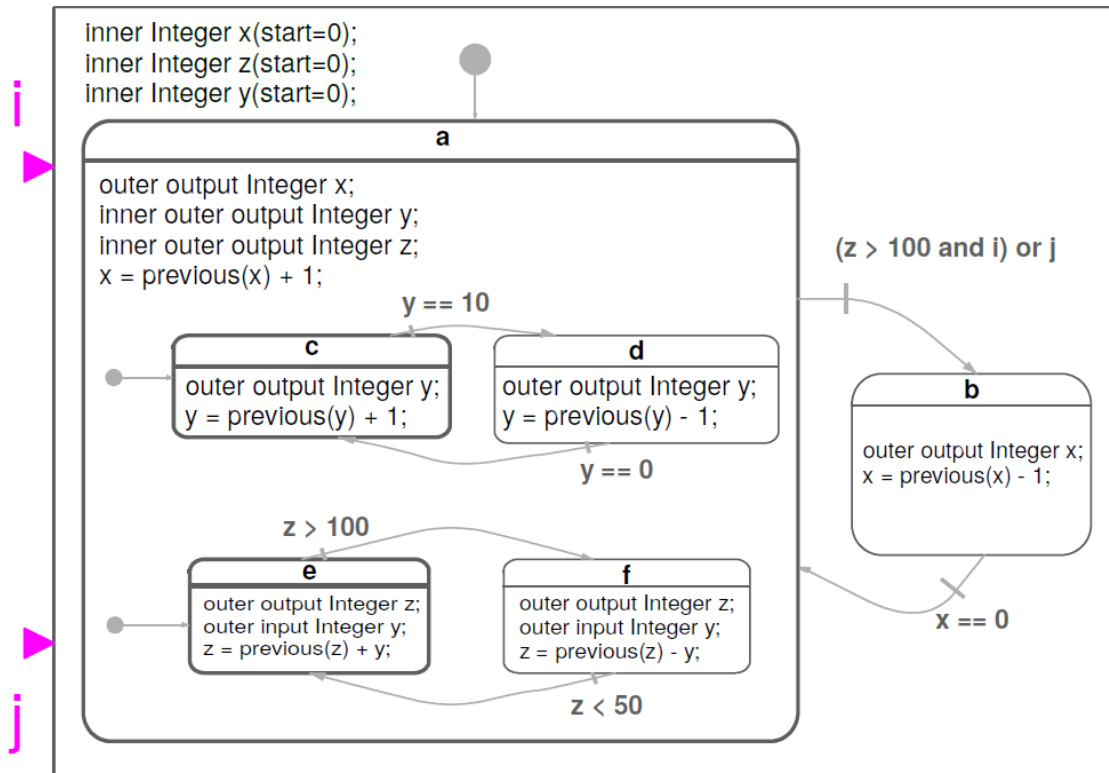
```
model Simple_NoAnnotations "Simple state machine"
  inner Integer i(start=0);
  block State1
    outer output Integer i;
    output Integer j(start=10);
  equation
    i = previous(i) + 2;
    j = previous(j) - 1;
  end State1;
  State1 state1;
  block State2
    outer output Integer i;
  equation
    i = previous(i) - 1;
  end State2;
  State2 state2;
equation
  transition(state1, state2, i > 10, immediate=false);
  transition(state2, state1, i < 1, immediate=false);
  initialState(state1);
end Simple_NoAnnotations;
```

Hierarchical and Parallel Composition of Modelica State Machine Models



Semantics of Modelica state machines (and example above) inspired by Florence Maraninchi & Yann Rémond's "Mode-Automata" and by Marc Pouzet's Lucid Synchrone 3.0.

Hierarchical and Parallel Composition

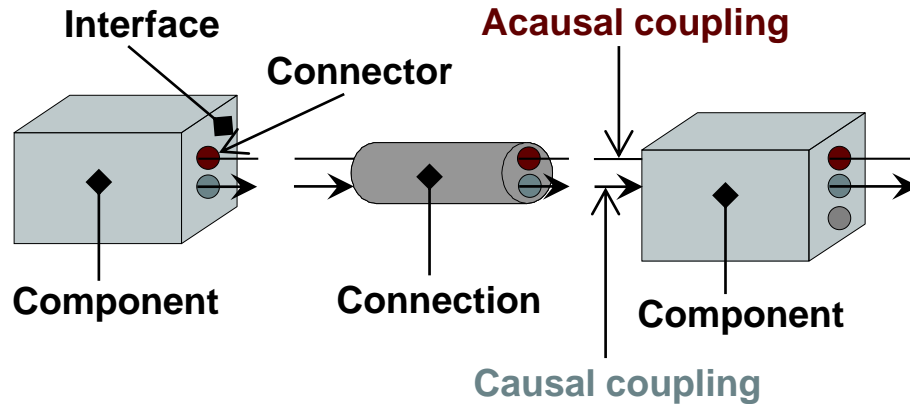


Semantics of Modelica state machines (and example above) inspired by Florence Maraninchi & Yann Rémond's "Mode-Automata" and by Marc Pouzet's Lucid Synchrone 3.0.

Part IV

Components, Connectors and Connections – Modelica Libraries and Graphical Modeling

Software Component Model



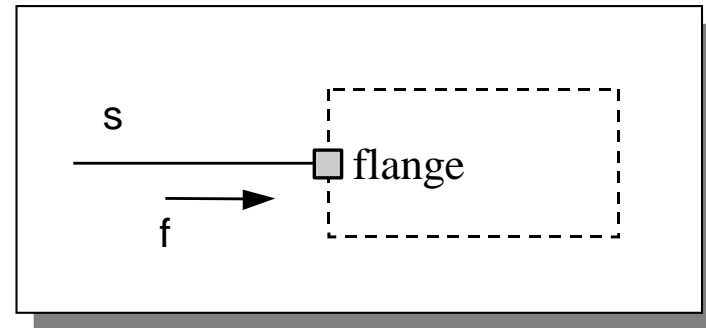
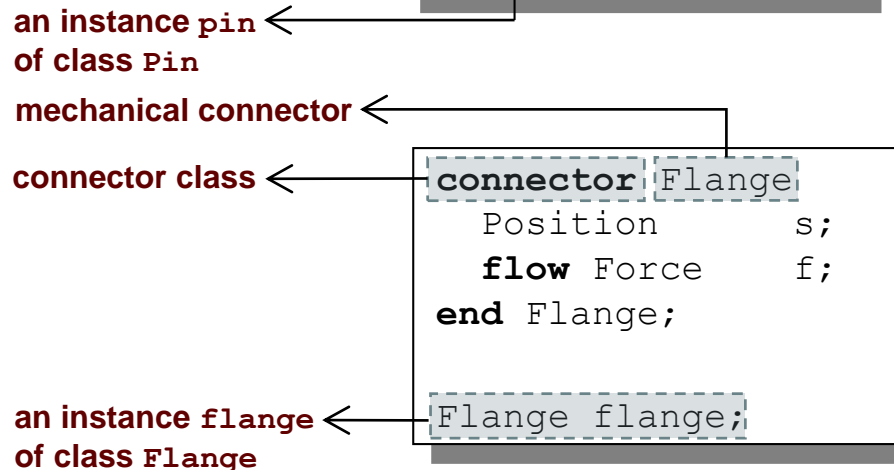
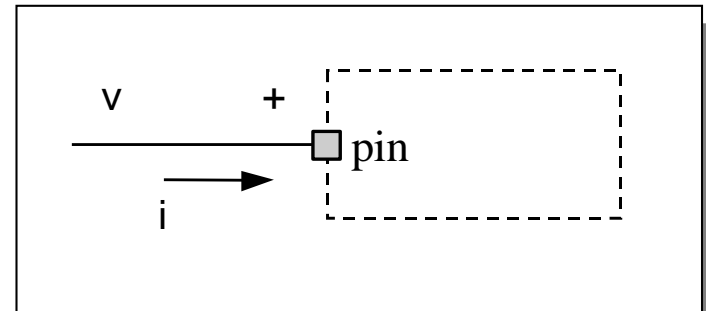
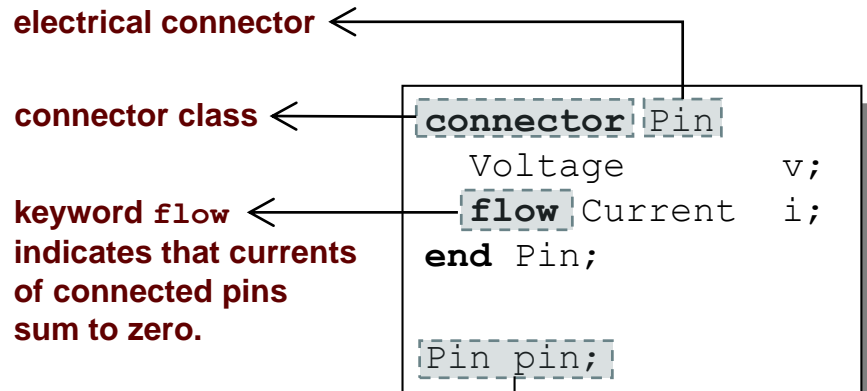
A component class should be defined *independently of the environment*, very essential for *reusability*

A component may internally consist of other components, i.e. *hierarchical* modeling

Complex systems usually consist of large numbers of *connected* components

Connectors and Connector Classes

Connectors are instances of *connector classes*



The `flow` prefix

Three possible kinds of variables in connectors:

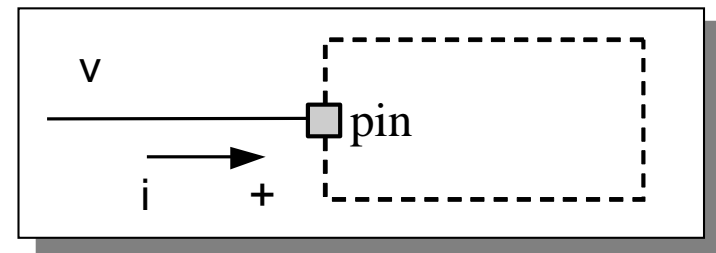
- *Potential variables* *potential* or energy level
- *Flow variables* represent some kind of flow
- *Stream variables* represent fluid flow in convective transport

Coupling

- *Equality coupling*, for potential variables
- *Sum-to-zero coupling*, for `flow` variables

The value of a `flow` variable is *positive* when the current or the flow is *into* the component

positive flow direction:



Physical Connector Classes Based on Energy Flow

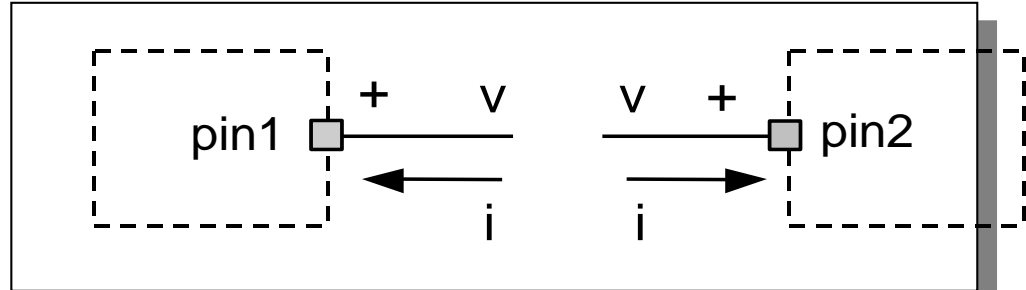
| Domain Type | Potential | Flow | Carrier | Modelica Library |
|---------------|--------------------|--------------------|------------------|------------------------------|
| Electrical | Voltage | Current | Charge | Electrical. Analog |
| Translational | Position | Force | Linear momentum | Mechanical. Translational |
| Rotational | Angle | Torque | Angular momentum | Mechanical. Rotational |
| Magnetic | Magnetic potential | Magnetic flux rate | Magnetic flux | Magnetic |
| Hydraulic | Pressure | Volume flow | Volume | OpenHydraulics |
| Heat | Temperature | Heat flow | Heat | HeatFlow1D |
| Chemical | Chemical potential | Particle flow | Particles | Chemical |
| Pneumatic | Pressure | Mass flow | Air | PneuLibLight |

connect-equations

Connections between connectors are realized as *equations* in Modelica

```
connect (connector1,connector2)
```

The two arguments of a `connect`-equation must be references to *connectors*, either to be declared directly *within* the same class or be *members* of one of the declared variables in that class



```
Pin pin1, pin2;  
//A connect equation  
//in Modelica:  
connect (pin1, pin2);
```

Corresponds to

```
pin1.v = pin2.v;  
pin1.i + pin2.i = 0;
```

Connection Equations

```
Pin pin1, pin2;  
//A connect equation  
//in Modelica  
connect(pin1, pin2);
```

Corresponds to

```
pin1.v = pin2.v;  
pin1.i + pin2.i = 0;
```

Multiple connections are possible:

```
connect(pin1, pin2); connect(pin1, pin3); ... connect(pin1, pinN);
```

Each primitive connection set of **potential** variables is used to generate equations of the form:

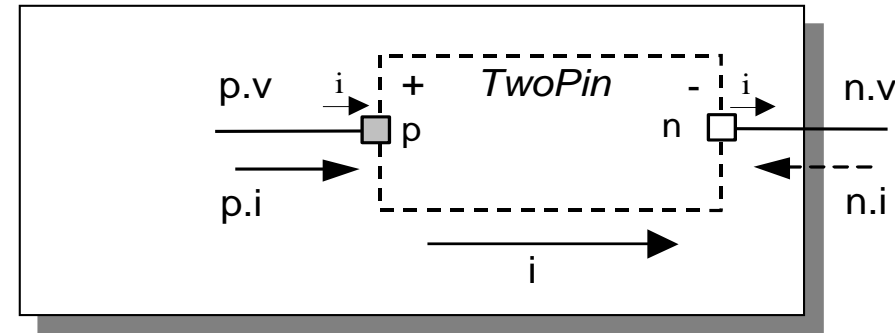
$$V_1 = V_2 = V_3 = \dots V_n$$

Each primitive connection set of **flow** variables is used to generate *sum-to-zero* equations of the form:

$$i_1 + i_2 + \dots (-i_k) + \dots i_n = 0$$

Common Component Structure

The base class `TwoPin` has two connectors `p` and `n` for positive and negative pins respectively



partial class
(cannot be
instantiated)

positive pin
negative pin

```
partial model TwoPin
  Voltage v
  Current i
  Pin p;
  Pin n;
equation
  v = p.v - n.v;
  0 = p.i + n.i;
  i = p.i;
end TwoPin;
// TwoPin is same as OnePort in
// Modelica.Electrical.Analog.Interfaces
```

```
connector Pin
  Voltage v;
  flow Current i;
end Pin;
```

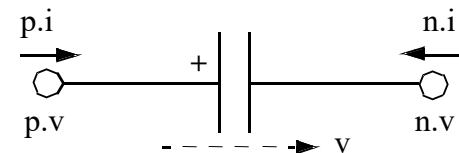
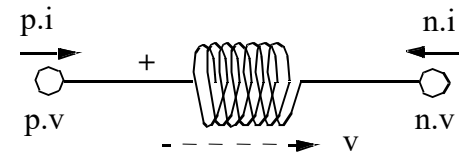
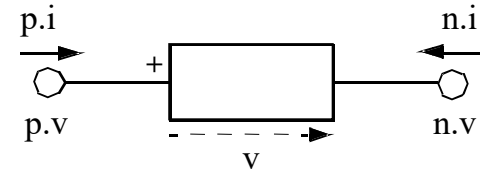
electrical connector class

Electrical Components

```
model Resistor "Ideal electrical resistor"  
  extends TwoPin;  
  parameter Real R;  
equation  
   $R*i = v$ ;  
end Resistor;
```

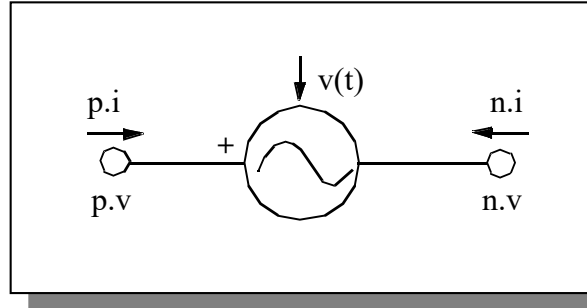
```
model Inductor "Ideal electrical inductor"  
  extends TwoPin;  
  parameter Real L "Inductance";  
equation  
   $L*der(i) = v$ ;  
end Inductor;
```

```
model Capacitor "Ideal electrical capacitor"  
  extends TwoPin;  
  parameter Real C ;  
equation  
   $i=C*der(v)$ ;  
end Capacitor;
```

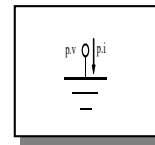


Electrical Components cont'

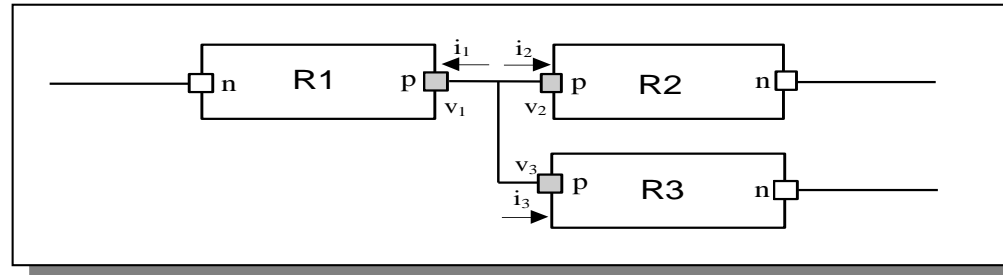
```
model Source
  extends TwoPin;
  parameter Real A,w;
equation
  v = A*sin(w*time);
end Resistor;
```



```
model Ground
  Pin p;
equation
  p.v = 0;
end Ground;
```



Resistor Circuit



```
model ResistorCircuit
  Resistor R1 (R=100);
  Resistor R2 (R=200);
  Resistor R3 (R=300);
equation
  connect (R1.p, R2.p);
  connect (R1.p, R3.p);
end ResistorCircuit;
```

Corresponds to

```
R1.p.v = R2.p.v;
R1.p.v = R3.p.v;
R1.p.i + R2.p.i + R3.p.i = 0;
```

Modelica Standard Library - Graphical Modeling

- *Modelica Standard Library* (called Modelica) is a standardized predefined package developed by Modelica Association
- It can be used freely for both commercial and noncommercial purposes under the conditions of *The Modelica License*.
- Modelica libraries are available online including documentation and source code from <http://www.modelica.org/library/library.html>

Modelica Standard Library cont'

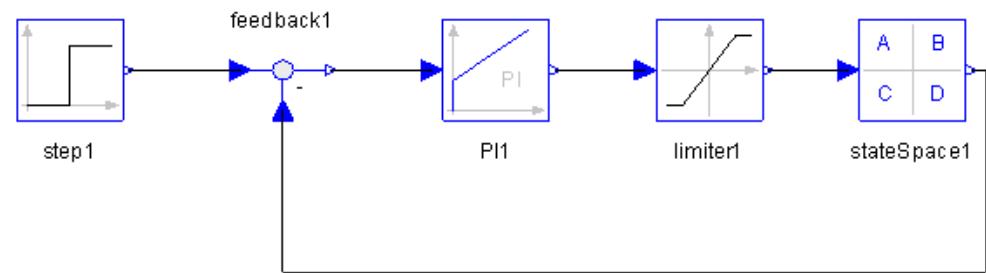
The Modelica Standard Library contains components from various application areas, including the following sublibraries:

- **Blocks** Library for basic input/output control blocks
- **Constants** Mathematical constants and constants of nature
- **Electrical** Library for electrical models
- **Icons** Icon definitions
- **Fluid** 1-dim Flow in networks of vessels, pipes, fluid machines, valves, etc.
- **Math** Mathematical functions
- **Magnetic** Magnetic – for magnetic applications
- **Mechanics** Library for mechanical systems
- **Media** Media models for liquids and gases
- **Slunits** Type definitions based on SI units according to ISO 31-1992
- **Stategraph** Hierarchical state machines (analogous to Statecharts)
- **Thermal** Components for thermal systems
- **Utilities** Utility functions especially for scripting

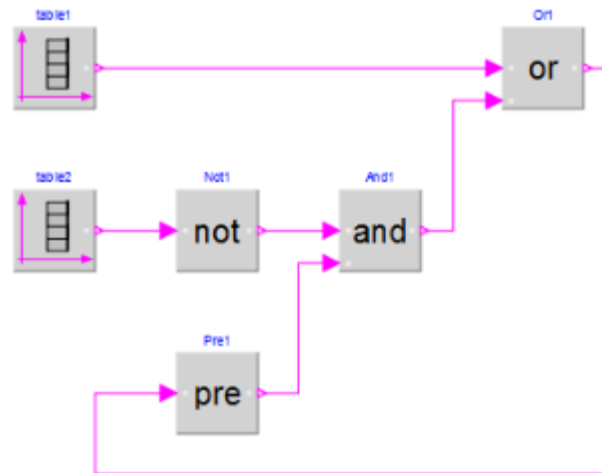
Modelica.Blocks

- Modelica
 - Blocks
 - Continuous
 - Discrete
 - Examples
 - Interfaces
 - Logical
 - Math
 - Nonlinear
 - Routing
 - Sources
 - Tables
 - Types
 - Constants
 - Electrical
 - Icons
 - Math
 - Mechanics
 - SIunits
 - StateGraph
 - Thermal

Continuous, discrete, and logical input/output blocks to build block diagrams.

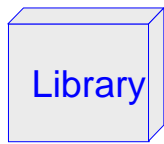


Examples:

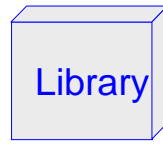


Modelica.Electrical

Electrical components for building analog, digital, and multiphase circuits



Analog



Digital

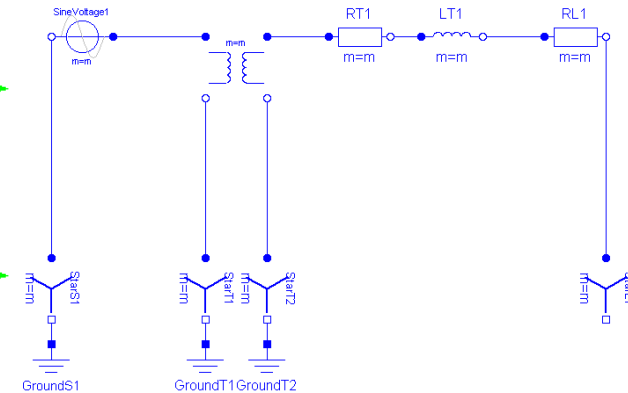
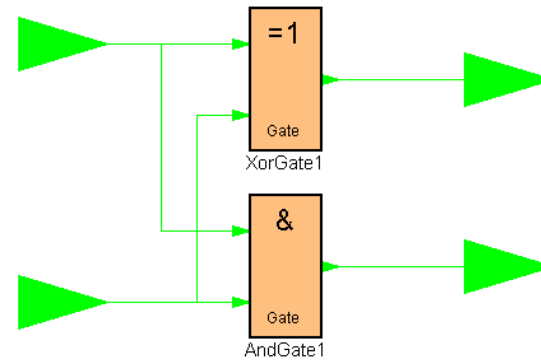
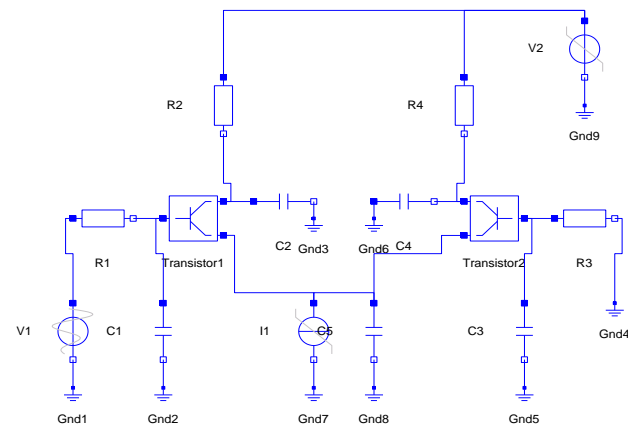


Machines



MultiPhase

Examples:

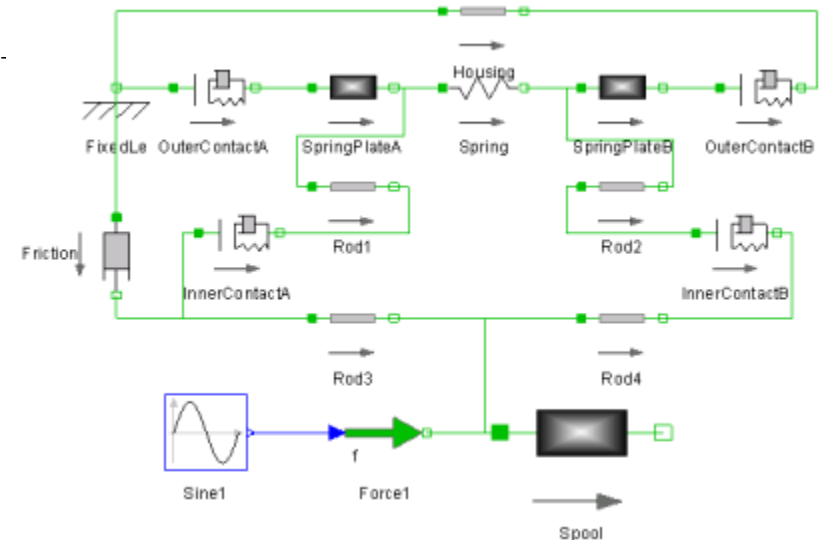
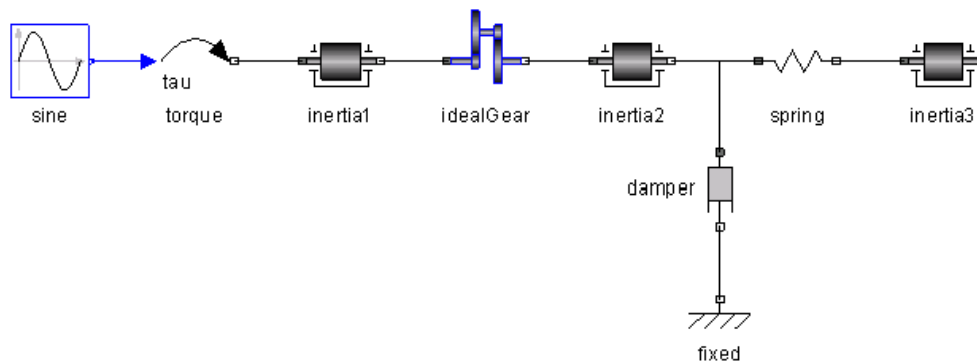


Modelica.Mechanics

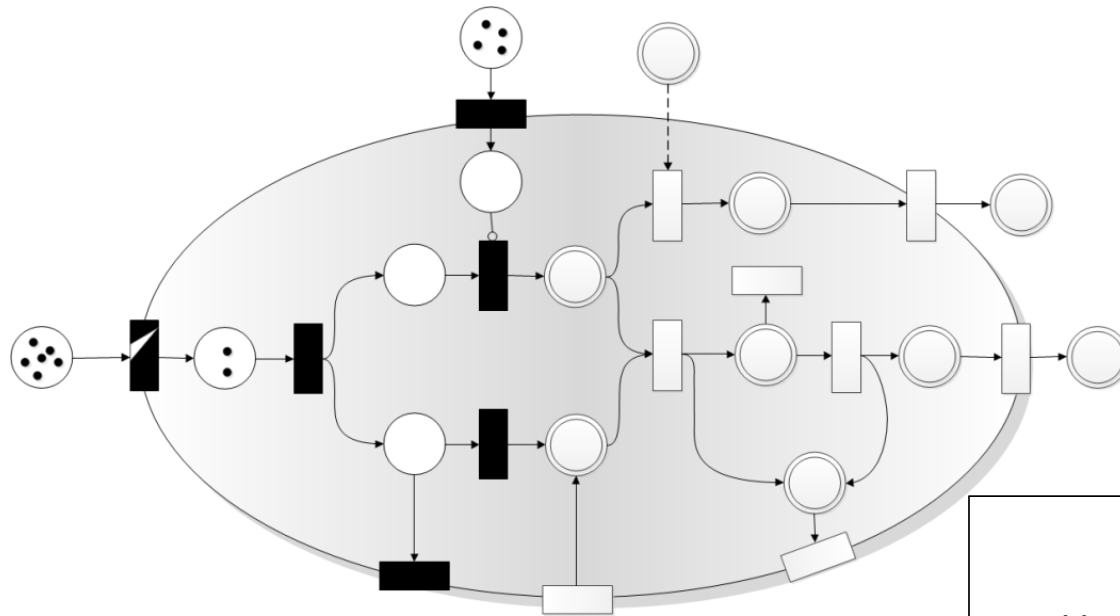
Package containing components for mechanical systems

Subpackages:

- Rotational 1-dimensional rotational mechanical components
- Translational 1-dimensional translational mechanical components
- MultiBody 3-dimensional mechanical components






PNlib - An Advanced Petri Net Library for Hybrid Process Modeling





xHPN: Extended Hybrid Petri Nets





Transitions

-  (time-)discrete process (event)
-  stochastic process (random event)
-  continuous process (flow)

Places

-  (time-)discrete state (integer quantity)
-  continuous state (real quantity)

Arcs

-  „normal“ arc
-  inhibitor arc
-  test arc
-  read arc

Other Free Libraries

Up to date list at: <https://www.modelica.org/libraries>

- WasteWater Wastewater treatment plants, 2003
- ATPlus Building simulation and control (fuzzy control included), 2005
- MotorCycleDynamics Dynamics and control of motorcycles, 2009
- NeuralNetwork Neural network mathematical models, 2006
- VehicleDynamics Dynamics of vehicle chassis (obsolete), 2003
- SPICElib Some capabilities of electric circuit simulator PSPICE, 2003
- SystemDynamics System dynamics modeling a la J. Forrester, 2007
- BondLib Bond graph modeling of physical systems, 2007
- MultiBondLib Multi bond graph modeling of physical systems, 2007
- ModelicaDEVS DEVS discrete event modeling, 2006
- ExtendedPetriNets Petri net modeling, 2002
- External.Media Library External fluid property computation, 2008
- VirtualLabBuilder Implementation of virtual labs, 2007
- PowerSystems Power systems in transient and steady-state mode
- ...

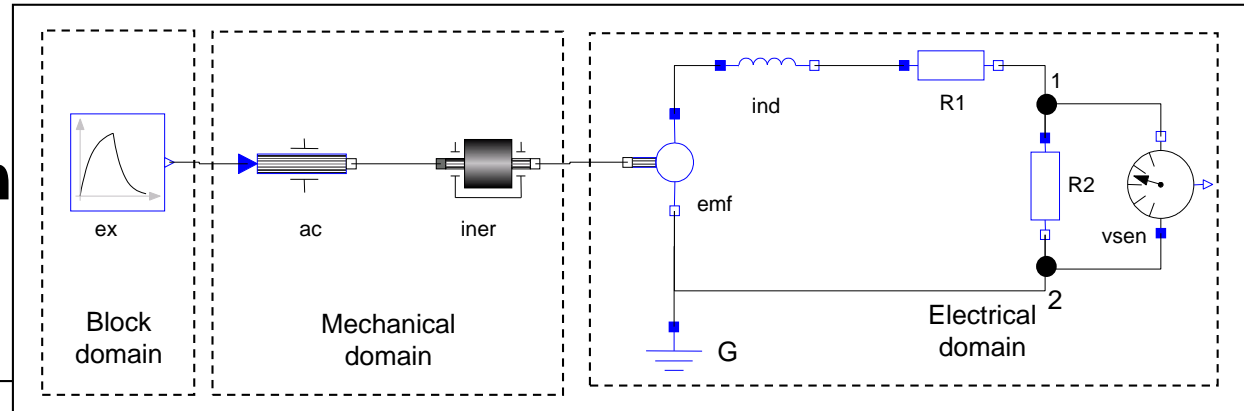
Some Commercial Libraries

Up to date list at: <https://www.modelica.org/libraries>

- Air Conditioning
- Electric Power
- Fuel Cell
- Heat Exchanger
- Hydro Power
- Liquid Cooling
- Thermal Power
- Vapor Cycle
- Battery
- Belts
- Engine
- ...
- Powertrain
- SmartElectricDrives
- VehicleDynamics
- Hydraulics
- Pneumatics
- Engine Dynamics
- Environmental Control
- CombiPlant
- ...
- (there are many more)

Connecting Components from Multiple Domains

- Block domain
- Mechanical domain
- Electrical domain



model Generator

```
Modelica.Mechanics.Rotational.Accelerate ac;  
Modelica.Mechanics.Rotational.Inertia iner;  
Modelica.Electrical.Analog.Basic.EMF emf(k=-1);  
Modelica.Electrical.Analog.Basic.Inductor ind(L=0.1);  
Modelica.Electrical.Analog.Basic.Resistor R1,R2;  
Modelica.Electrical.Analog.Basic.Ground G;  
Modelica.Electrical.Analog.Sensors.VoltageSensor vsens;  
Modelica.Blocks.Sources.Exponentials ex(riseTime={2},riseTimeConst={1});
```

equation

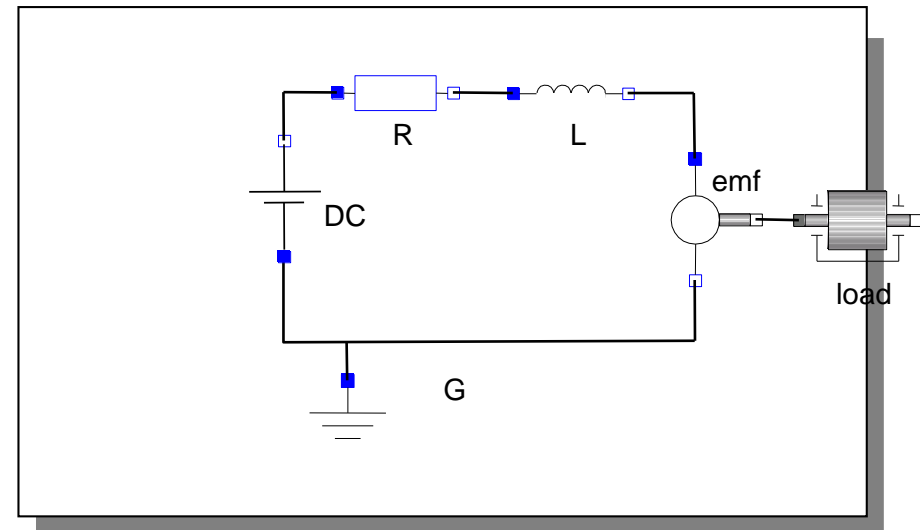
```
connect(ac.flange_b, iner.flange_a); connect(iner.flange_b, emf.flange_b);  
connect(emf.p, ind.p); connect(ind.n, R1.p); connect(emf.n, G.p);  
connect(emf.n, R2.n); connect(R1.n, R2.p); connect(R2.p, vsens.n);  
connect(R2.n, vsens.p); connect(ex.outPort, ac.inPort);
```

```
end Generator;
```

DCMotor Model Multi-Domain (Electro-Mechanical)

A DC motor can be thought of as an electrical circuit which also contains an electromechanical component.

```
model DCMotor
  Resistor R(R=100);
  Inductor L(L=100);
  VsourceDC DC(f=10);
  Ground G;
  EMF emf(k=10, J=10, b=2);
  Inertia load;
equation
  connect (DC.p, R.n);
  connect (R.p, L.n);
  connect (L.p, emf.n);
  connect (emf.p, DC.n);
  connect (DC.n, G.p);
  connect (emf.flange, load.flange);
end DCMotor;
```



Part IV

Sensitivity Analysis

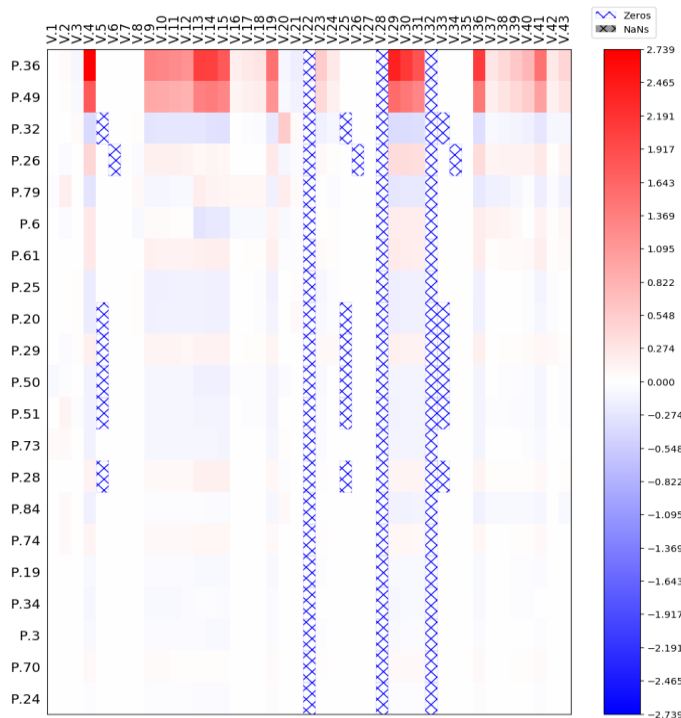
using

OpenModelica

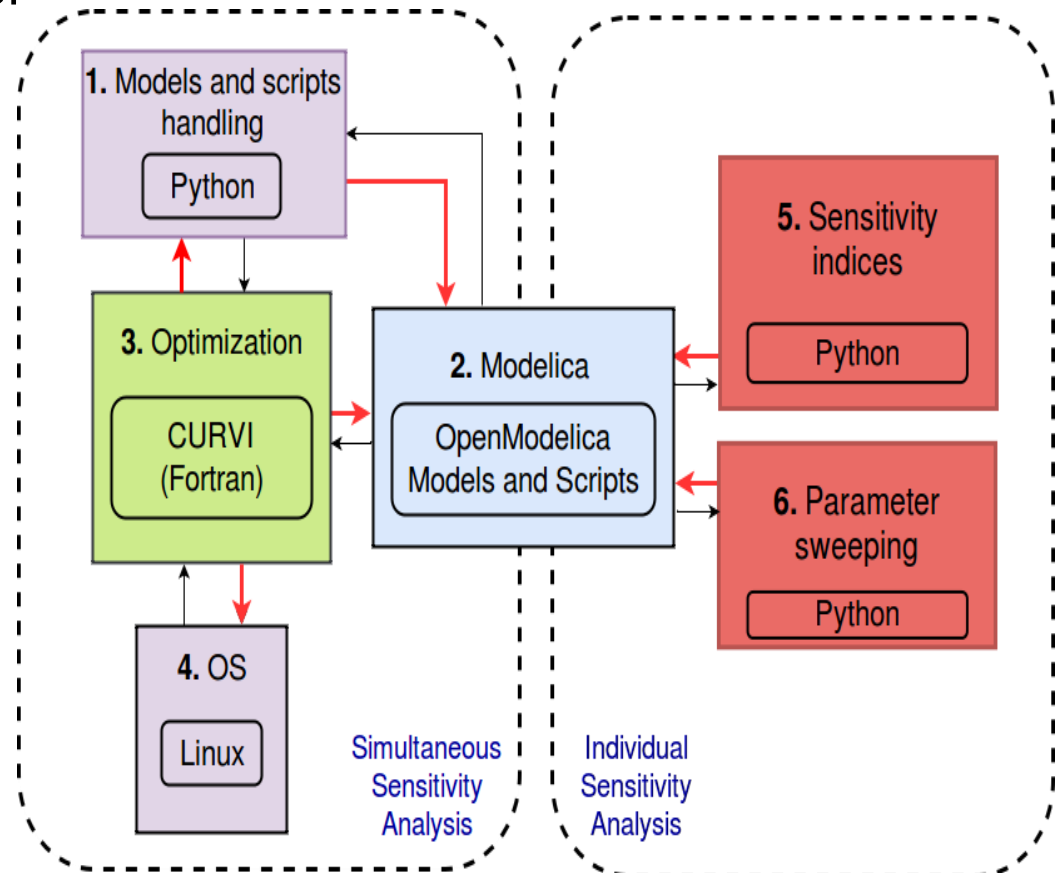
OMSens – Multi-Parameter Sensitivity Analysis

- Individual and simultaneous multi-parameter analysis
- Optimization-based simultaneous analysis
- Robust derivative free optimizer

Heatmap visualization

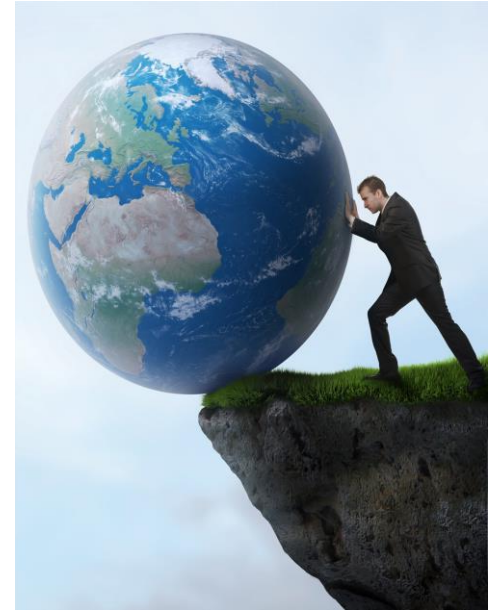


Tool architecture



Introduction to Sensitivity Analysis

- Sensitivity of nonlinear systems in the form of ODEs
 - Undergo noticeable **dynamic changes** in response to **small perturbations** in the parameters.
- OO-languages (Modelica)
 - Systematic treatment of the problem
 - Clear, unambiguous access to parameters, variables and simulation configuration.
 - Reusable frameworks to manipulate models as black boxes.
- Varied options to use internal knowledge about model structure



Approaches to Sensitivity Analysis

- **Individual** analysis:
 - **One parameter** perturbed at a time
 - Ignores combinations of perturbations
- **Simultaneous** analysis:
 - All possible combinations not feasible
 - Would give combinatorial explosion of parameter settings
 - Find “**optimal**” **combinations** of perturbations
 - “Smallest simultaneous perturbations that produce largest deviations”
 - Typically: **optimization-based** strategies

CURVIF: robust derivative-free optimization algorithm

- The CURVI family
 - Curvilinear search approach
- Three versions: CURVIF, CURVIG, CURVIH
 - Function values, function values plus Gradients, and the latter plus Hessians.
 - Globally convergent
 - In general uses **fewer evaluations** than other algorithms
- CURVIF: the flavor adopted for OMSens
 - Trade-off: favor **robustness**, sacrifice some efficiency
 - Derivative-free methods can either be robust - at the cost of using many function evaluations, e.g. direct searches - or may present convergence problems

LotkaVolterra – A Simple Model to be Used for Sensitivity Analysis Exercises

```
model LotkaVolterra "This is the typical equation-oriented model"  
  parameter Real alpha=0.1 "Reproduction rate of prey";  
  parameter Real beta=0.02 "Mortality rate of predator per prey";  
  parameter Real gamma=0.4 "Mortality rate of predator";  
  parameter Real delta=0.02 "Reproduction rate of predator per prey";  
  parameter Real prey_pop_init=10 "Initial prey population";  
  parameter Real pred_pop_init=10 "Initial predator population";  
  Real prey_pop(start=prey_pop_init) "Prey population";  
  Real pred_pop(start=pred_pop_init) "Predator population";  
initial equation  
  prey_pop = prey_pop_init;  
  pred_pop = pred_pop_init;  
equation  
  der(prey_pop) = prey_pop*(alpha-beta*pred_pop);  
  der(pred_pop) = pred_pop*(delta*prey_pop-gamma);  
end LotkaVolterra ;
```

Preparations for Sensitivity Analysis Exercises

Assuming that you already have latest OpenModelica nightly installed. (e.g.1.16.0)

NOTE: Change the paths according to your installation whenever needed in the following commands.

Step1. Install Anaconda (most easily in c:\anaconda3)

=====

For 64-bit use https://repo.anaconda.com/archive/Anaconda3-2019.10-Windows-x86_64.exe

For 32-bit use <https://repo.anaconda.com/archive/Anaconda3-2019.10-Windows-x86.exe>

Follow the installer and install using the default options i.e., don't change anything (we recommend installing in C:\Anaconda3).

Step 2. Install libpython

=====

Open windows command prompt CMD and type/copy the following commands,

(this is one line☺)

```
set PATH=C:\Anaconda3;C:\Anaconda3\Library\mingw-w64\bin\;C:\Anaconda3\Library\bin;C:\Anaconda3\Scripts;
```

```
C:\Program Files\OpenModelica1.16.0-dev-64bit\tools\msys\mingw64\bin;%PATH%
```

```
conda install libpython
```

Step 3. Compile OMSens Backend

=====

Use the same windows command prompt from last step and copy/run the commands (one at a time)

```
cd "C:\Program Files\OpenModelica1.16.0-dev-64bit\OMSens\fortran_interface"
```

```
gfortran -c Rutf.for Rut.for Curvif.for
```

```
f2py.exe -c -l Curvif.o Rutf.o Rut.o -m curvif_simplified curvif_simplified.pyf Curvif_simplified.f90 --compiler=mingw32
```

```
"C:\Program Files\OpenModelica1.16.0-dev-64bit\bin\OMEdit.exe"
```

Step 4: Run OMEdit with OMSens

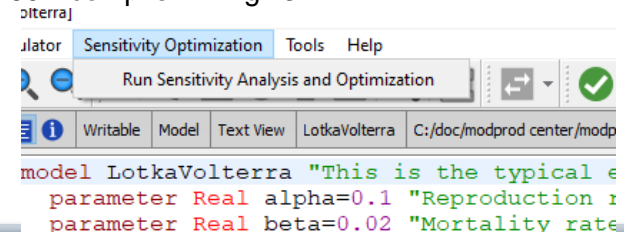
Now use the OMEdit we just started from the CMD command window (just push enter)

Load the LotkaVolterra model, open it, run it e.g. 100 seconds

and select the OMSens functionality from the top menu item i.e., "Sensitivity Optimization"

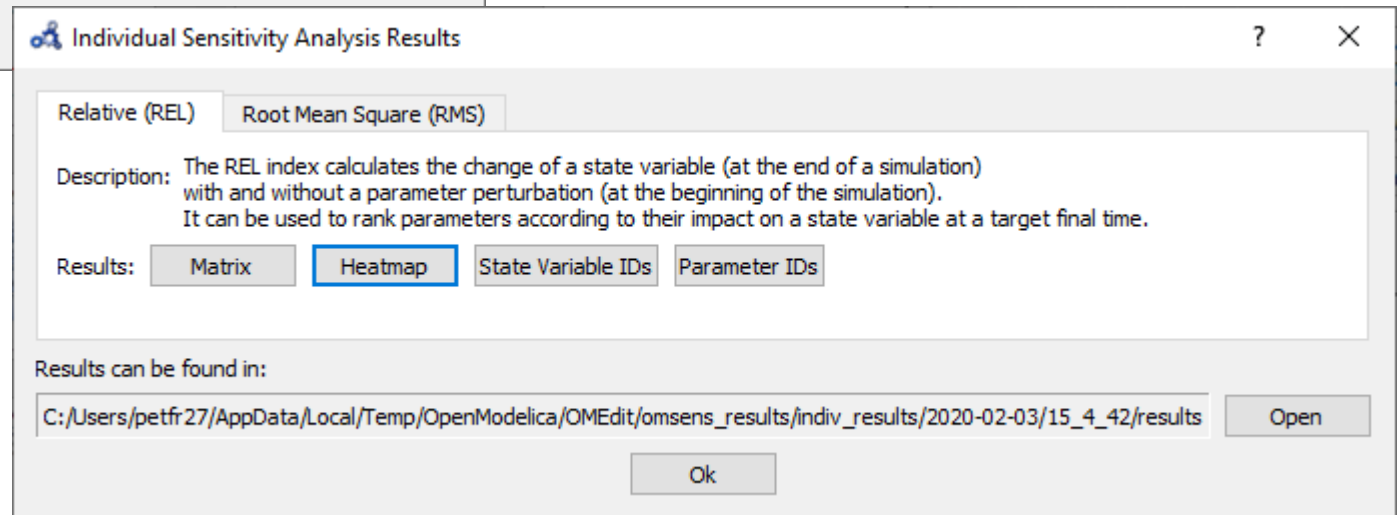
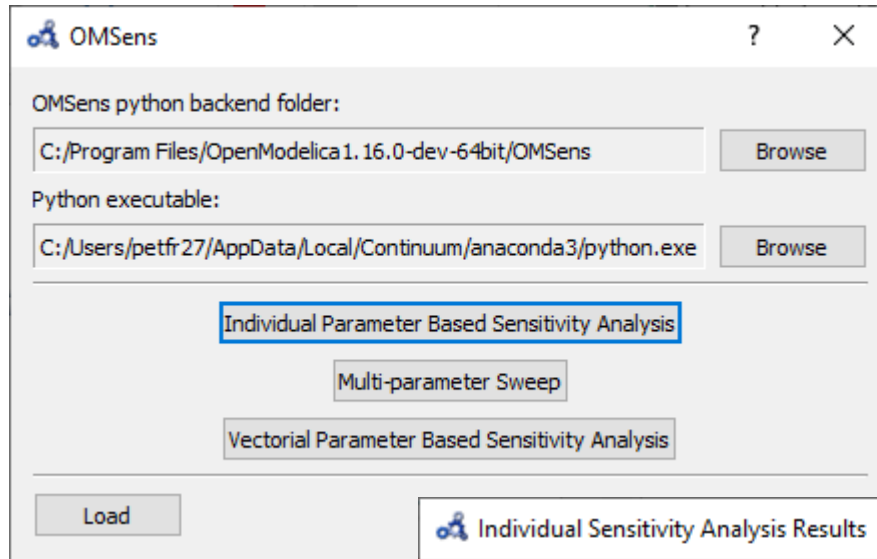
More info in the file:

OMSens Example_Exercise_Lotka-Volterra.pdf



OMSens Exercise – Locate Python

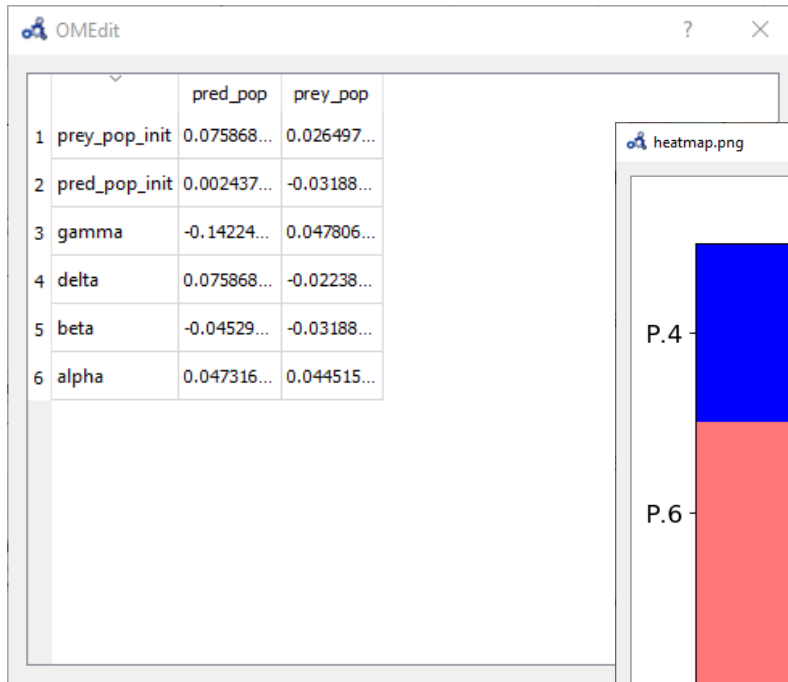
Select Analysis type



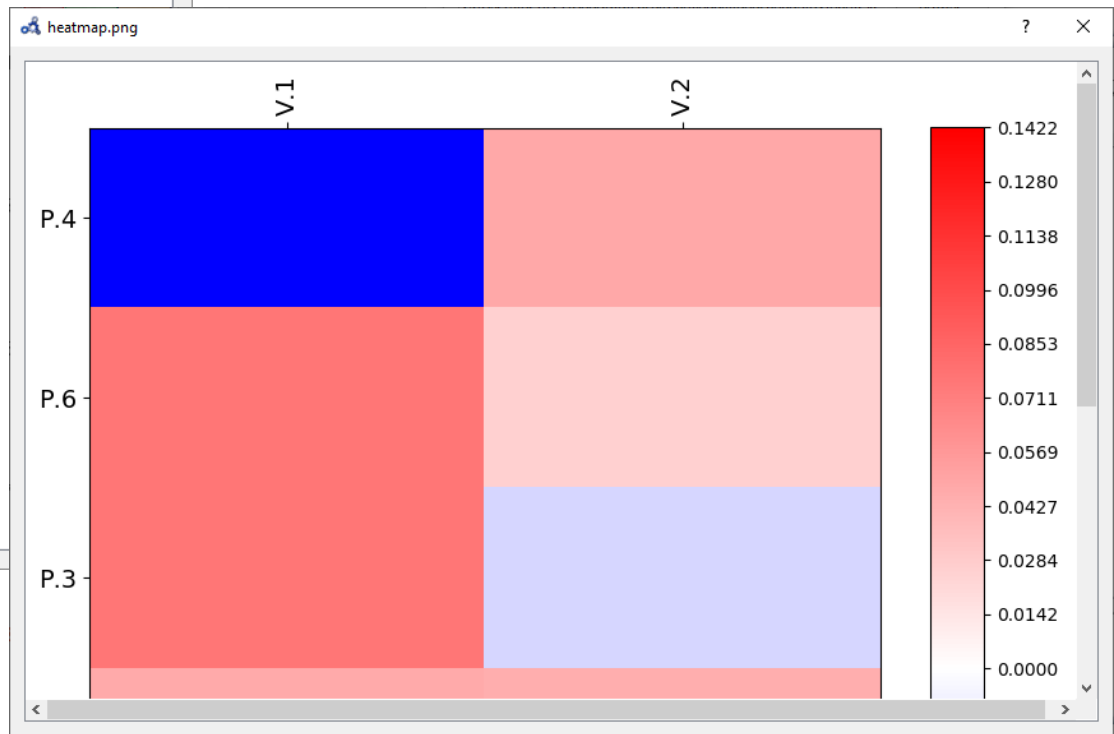
OMSens Exercise –results from individual analysis

More info in the file:

OMSens Example_Exercise_ Lotka-Volterra.pdf



| | pred_pop | prey_pop |
|-----------------|-------------|-------------|
| 1 prey_pop_init | 0.075868... | 0.026497... |
| 2 pred_pop_init | 0.002437... | -0.03188... |
| 3 gamma | -0.14224... | 0.047806... |
| 4 delta | 0.075868... | -0.02238... |
| 5 beta | -0.04529... | -0.03188... |
| 6 alpha | 0.047316... | 0.044515... |



Part Vb
More
Graphical Modeling Exercises

using
OpenModelica

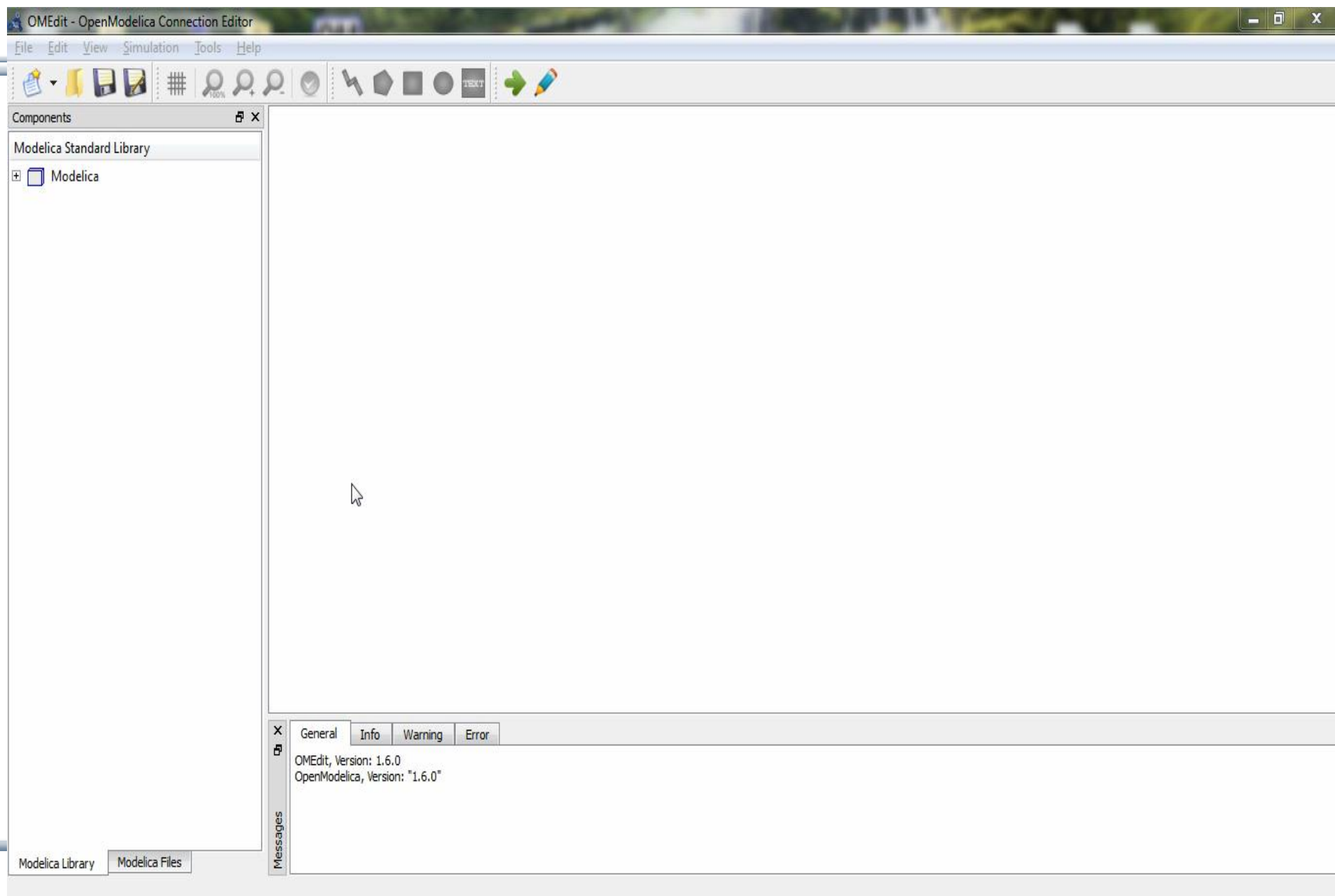
Graphical Modeling - Using Drag and Drop Composition

The screenshot displays the OMEdit - OpenModelica Connection Editor interface. The main workspace shows a circuit diagram for a DC motor model. The circuit consists of a step input block labeled 'step1' with 'startTime=0', connected to a voltage source 'signalVoltage1'. This is followed by a resistor 'resistor1' with resistance 'R=R', an inductor 'inductor1' with inductance 'L=L', and a motor component 'emf' with moment of inertia 'J=J'. The circuit is connected to a ground 'ground1'.

The Variables Browser on the right shows the state of the DCMotor model. The variables and their values are as follows:

| Variable | Value | Unit |
|-----------------|-----------|-------|
| emf | | |
| der(phi) | -0.3403 | deg |
| fixed | | |
| flange | | |
| i | -0.533507 | A |
| internalSupport | | |
| k | 1.0 | N.m/ |
| n | | |
| p | | |
| phi | | deg |
| useSupport | 0 | |
| v | -0.3403 | V |
| w | -0.3403 | rad/s |
| ground1 | | |
| inductor1 | | |

Graphical Modeling Animation – DCMotor



Multi-Domain (Electro-Mechanical) Modelica Model

- A DC motor can be thought of as an electrical circuit which also contains an electromechanical component

model DCMotor

```
Resistor R(R=100);
```

```
Inductor L(L=100);
```

```
VsourceDC DC(f=10);
```

```
Ground G;
```

```
ElectroMechanicalElement EM(k=10, J=10, b=2);
```

```
Inertia load;
```

equation

```
connect (DC.p, R.n);
```

```
connect (R.p, L.n);
```

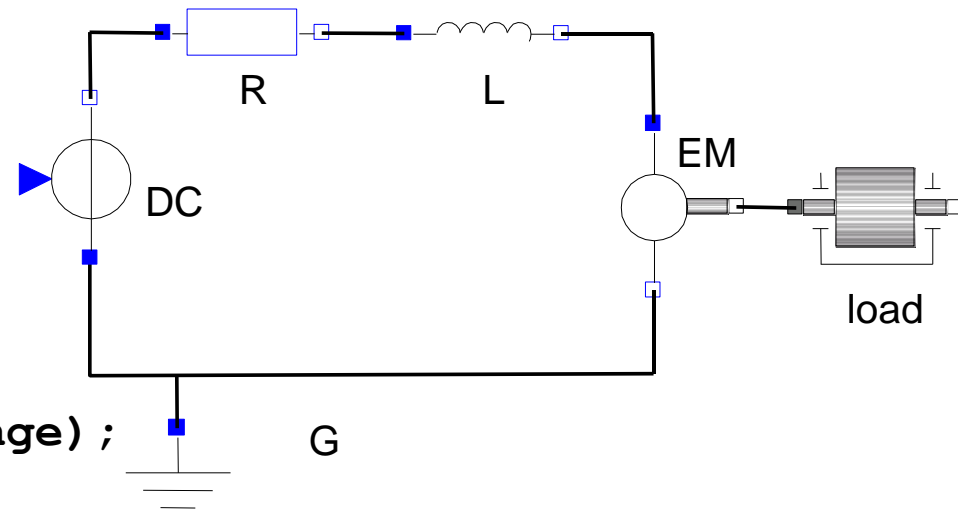
```
connect (L.p, EM.n);
```

```
connect (EM.p, DC.n);
```

```
connect (DC.n, G.p);
```

```
connect (EM.flange, load.flange);
```

end DCMotor



Corresponding DCMotor Model Equations

The following equations are automatically derived from the Modelica model:

| | | |
|------------------------|---|------------------------|
| $0 == DC.p.i + R.n.i$ | $EM.u == EM.p.v - EM.n.v$ | $R.u == R.p.v - R.n.v$ |
| $DC.p.v == R.n.v$ | $0 == EM.p.i + EM.n.i$ | $0 == R.p.i + R.n.i$ |
| | $EM.i == EM.p.i$ | $R.i == R.p.i$ |
| $0 == R.p.i + L.n.i$ | $EM.u == EM.k * EM.\omega$ | $R.u == R.R * R.i$ |
| $R.p.v == L.n.v$ | $EM.i == EM.M / EM.k$ | |
| | $EM.J * EM.\omega == EM.M - EM.b * EM.\omega$ | $L.u == L.p.v - L.n.v$ |
| $0 == L.p.i + EM.n.i$ | | $0 == L.p.i + L.n.i$ |
| $L.p.v == EM.n.v$ | $DC.u == DC.p.v - DC.n.v$ | $L.i == L.p.i$ |
| | $0 == DC.p.i + DC.n.i$ | $L.u == L.L * L.i'$ |
| $0 == EM.p.i + DC.n.i$ | $DC.i == DC.p.i$ | |
| $EM.p.v == DC.n.v$ | $DC.u == DC.Amp * Sin[2 \pi DC.f * t]$ | |
| $0 == DC.n.i + G.p.i$ | | |
| $DC.n.v == G.p.v$ | | |

(load component not included)

Automatic transformation to ODE or DAE for simulation:

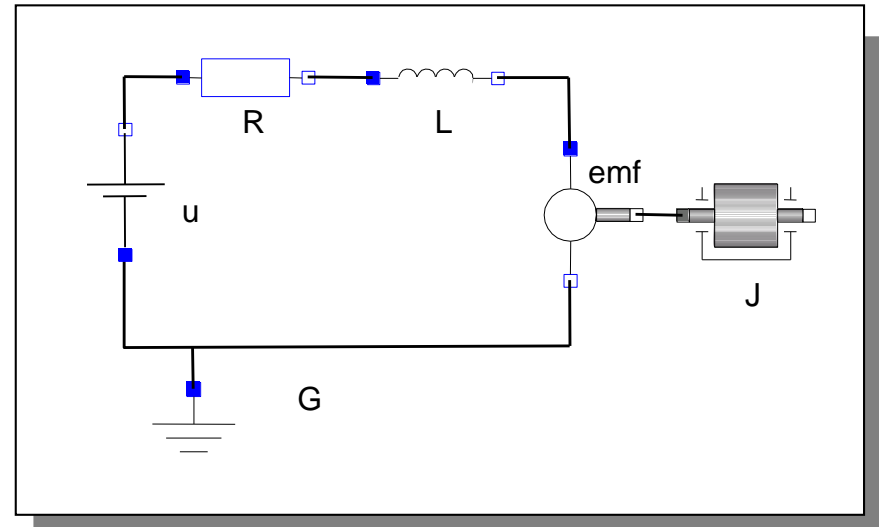
$$\frac{dx}{dt} == f[x, u, t] \quad g\left[\frac{dx}{dt}, x, u, t\right] == 0$$

Exercise 3.1

- Draw the `DCMotor` model using the graphic connection editor using models from the following Modelica libraries:

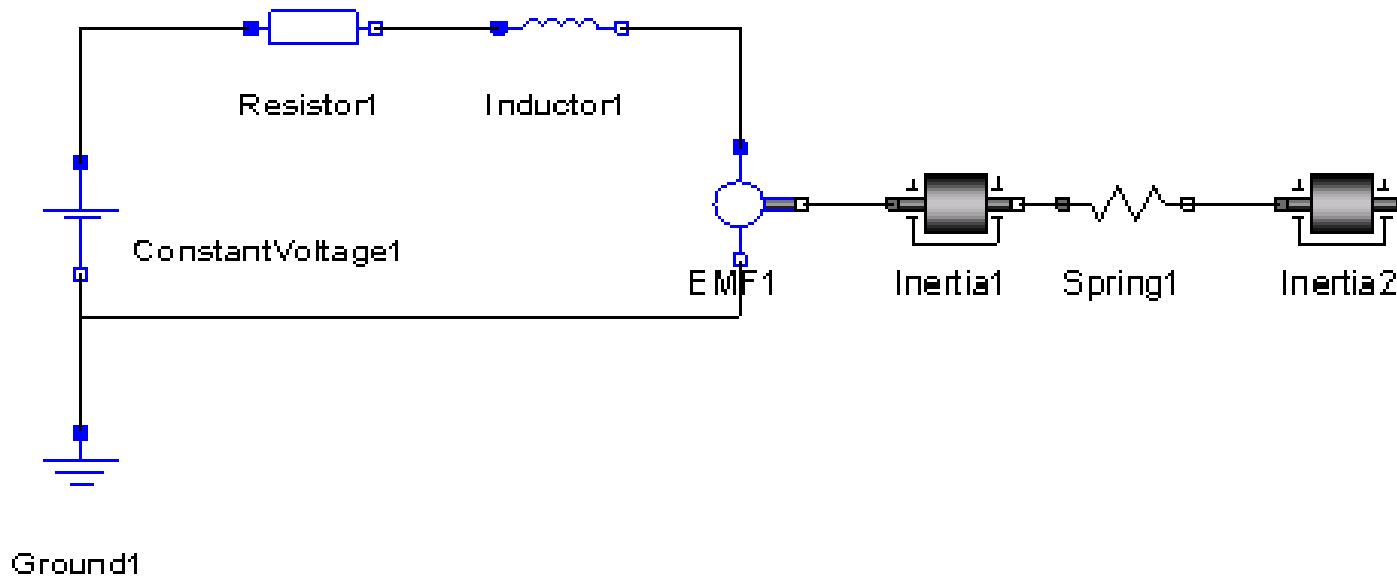
`Mechanics.Rotational.Components,`
`Electrical.Analog.Basic,`
`Electrical.Analog.Sources`

- Simulate it for 15s and plot the variables for the outgoing rotational speed on the inertia axis and the voltage on the voltage source (denoted `u` in the figure) in the same plot.



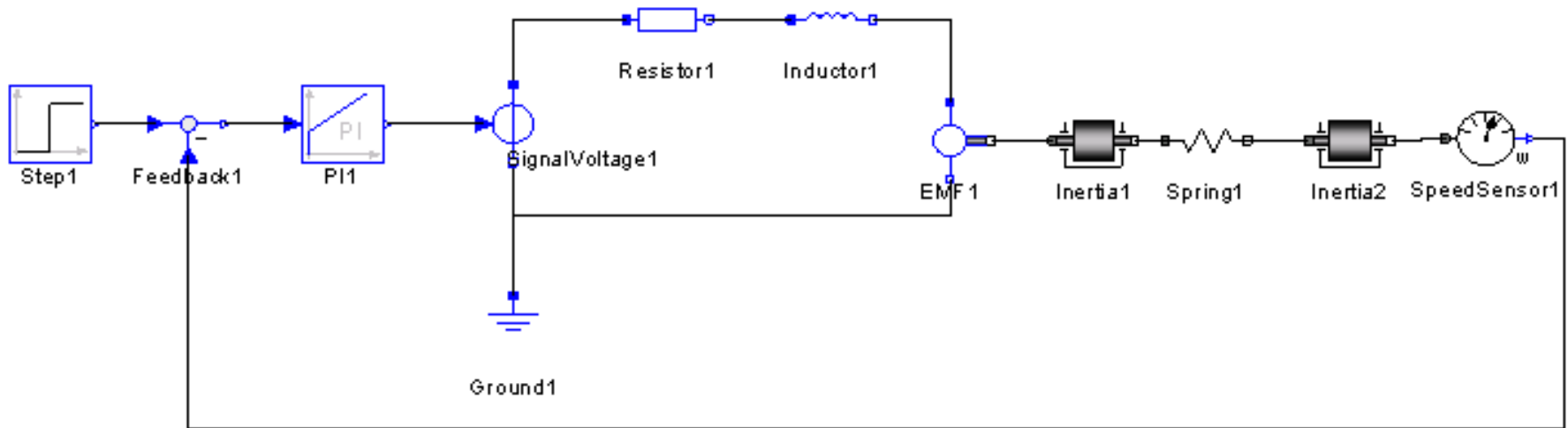
Exercise 3.2

- If there is enough time: Add a torsional spring to the outgoing shaft and another inertia element. Simulate again and see the results. Adjust some parameters to make a rather stiff spring.

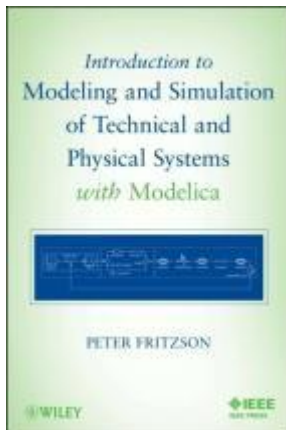
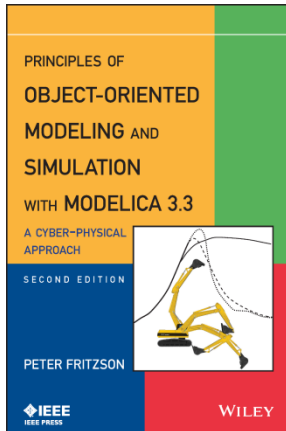


Exercise 3.3

- If there is enough time: Add a PI controller to the system and try to control the rotational speed of the outgoing shaft. Verify the result using a step signal for input. Tune the PI controller by changing its parameters in OMEdit.



Learn more...

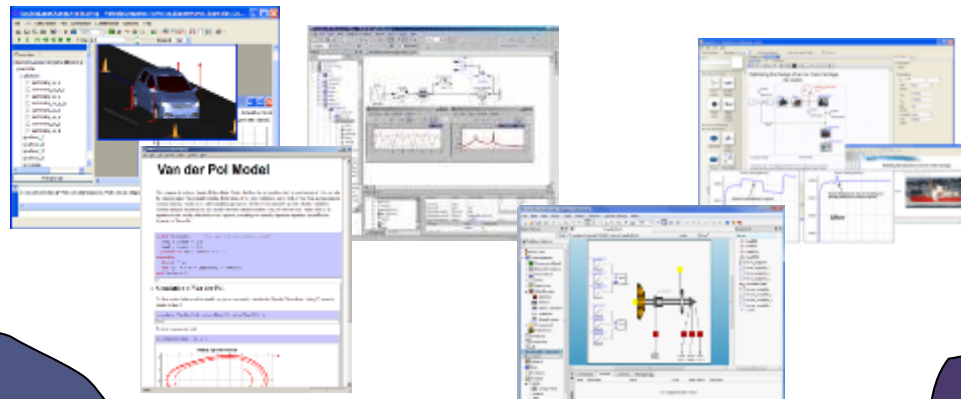


- OpenModelica
 - www.openmodelica.org
- Modelica Association
 - www.modelica.org
- Books
 - Principles of Object Oriented Modeling and Simulation with Modelica 3.3: A Cyber-Physical Approach, Peter Fritzson 2015.
 - Modeling and Simulation of Technical and Physical Systems with Modelica. Peter Fritzson., 2011
<http://eu.wiley.com/WileyCDA/WileyTitle/productCd-111801068X.html>
 - Introduction to Modelica, Michael Tiller

Summary

Multi-Domain
Modeling

Visual Acausal
Component
Modeling



Typed
Declarative
Textual Language

Thanks for listening!

Hybrid
Modeling