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1.1 Introduction

PSIM\textsuperscript{1} is a simulation software specifically designed for power electronics, motor drives, and power conversion systems. With fast simulation speed and friendly user interface, PSIM provides a powerful simulation environment to meet your simulation and development needs.

PSIM includes the basic package, as well as the following add-on options:

- **Motor Drive Module:** Built-in electric machine models and mechanical load models for motor drive system studies.
- **Digital Control Module:** Discrete library elements such as zero-order hold, z-domain transfer function blocks, quantization blocks, digital filters, for digital control system analysis.
- **SimCoupler Module:** Interface between PSIM and Matlab/Simulink\textsuperscript{2} for co-simulation.
- **Thermal Module:** Library elements and functions calculate semiconductor device losses and inductor losses.
- **Renewable Energy Module:** Library elements, such as solar module, wind turbine, battery, and ultra-capacitor models, for renewable energy applications.
- **SimCoder\textsuperscript{3} Module:** Function for automatic code generation capability.
- **F2833x Target:** Library elements for automatic code generation for TI F2833x series DSP.
- **F2803x Target:** Library elements for automatic code generation for TI F2803x series DSP.
- **KV3x Target:** Library elements for automatic code generation for Freescale KV3x series MCU.
- **PIL Module:** Interface between PSIM and TI DSP hardware boards for Processor-In-the-Loop (PIL) simulation.
- **MagCoupler Module:** Interface between PSIM and the electromagnetic field analysis software JMAG\textsuperscript{4} for co-simulation.
- **MagCoupler-RT Module:** Link between PSIM and JMAG-RT\textsuperscript{4} data files.
- **ModCoupler\textsuperscript{5} Modules:** Interface between PSIM and ModelSim\textsuperscript{6} for co-simulation. There are two versions of the interface: ModCoupler-VHDL that supports VHDL code, and ModCoupler-Verilog that supports Verilog code.
- **Motor Control Design Suite:** Pre-built templates for induction motor and linear/nonlinear PMSM drives.
- **HEV Design Suite:** Pre-built templates for hybrid electric vehicle (HEV) powertrain system design.

In addition, a link is provided between PSIM and CosiMate\textsuperscript{7}, a co-simulation framework that supports various software such as Matlab/Simulink, ModelSim, Saber (from Synopsys), Easy5 and Adams (from MSC Software), Inventor (from Autodesk), AMESim (from LMS), GT-Power (from Gamma Technologies), etc. Through CosiMate, PSIM can perform co-simulation with these software. For more information on CosiMate,
please visit www.chiastek.com.

Also, PSIM links with the software SmartCtrl for control loop design. SmartCtrl is designed specifically for power converter applications. For more information on SmartCtrl, please refer to SmartCtrl User’s Guide.

With these product lineup, Powersim provides a complete platform from design to simulation, to hardware implementation. The overall environment is shown in the figure below.

The PSIM simulation environment consists of the circuit schematic program PSIM, the simulator engine, and the waveform processing program SIMVIEW. The simulation process is illustrated as follows.

This manual covers both PSIM and all add-on Modules except the ones listed below which are covered by these documents respectively:

- SimCoder and all hardware Targets: SimCoder User Manual
- PIL Module: Tutorial - Processor-In-the-Loop Simulation.pdf

The organization of this manual is as follows:

- Chapter 1: PSIM circuit structure, software/hardware requirement, and parameter format.
- Chapter 2: PSIM environment and how to build a PSIM schematic.
1.2 **Circuit Structure**

A circuit is represented in PSIM in four blocks: power circuit, control circuit, sensors, and switch controllers. The figure below shows the relationship between these blocks.

![Circuit Structure Diagram](image)

The power circuit consists of switching devices, RLC branches, transformers, and coupled inductors. The control circuit is represented in block diagram. Components in s-domain and z-domain, logic components (such as logic gates and flip flops), and nonlinear components (such as multipliers and dividers) are used in the control circuit. Sensors are used to measure power circuit quantities and pass them to the control circuit. Gating signals are then generated from the control circuit and sent back to the power circuit through switch controllers to control switches.

1.3 **Software/Hardware Requirement**

PSIM runs in Microsoft Windows 7/8/10 on personal computers. The minimum RAM memory requirement is 1GB.

1.4 **Installing the Program**

A quick installation guide is provided in the flier “PSIM - Quick Guide” and on the CD-ROM.

Some of the files in the PSIM directory are:

- PSIM.exe: PSIM circuit schematic editor
- PcdEditor.exe: Device database editor
- SetSimPath.exe: Program to set up the SimCoupler Module

File extensions used in PSIM are:

- *.psimsch: PSIM schematic file
- *.psimpjt: PSIM project file
- *.lib: PSIM library file
- *.fra: PSIM ac analysis output file (text)
- *.dev: Device database file
- *.txt: Simulation output file in text format
1.5 Simulating a Circuit

To simulate the buck converter circuit “buck.psimsch” in "examples\dc-dc":
- Start PSIM. From the File menu, choose Open to load the file “buck.psimsch”.
- From the Simulate menu, choose Run PSIM to start the simulation. Simulation results will be saved to File “buck.smv”.
- By default, Auto-run SIMVIEW is selected in the Options menu. SIMVIEW will be launched automatically. In SIMVIEW, select curves for display. If this option is not selected, from the Simulate menu, choose Run SIMVIEW to start SIMVIEW.

1.6 Simulation Control

The Simulation Control element defines parameters and settings related to simulation.

To place the Simulation Control in the schematic, go to the Simulate menu, and select Simulation Control.

Image:

There are three tabs in the Simulation Control dialog:
- Parameters: Define essential parameters for transient simulation.
- SimCoder: Define the hardware for SimCoder simulation and automatic code generation. For more detailed information, please refer to SimCoder User's Manual.
- Color: Define the color of the Simulation Control image. The default color is blue.

<table>
<thead>
<tr>
<th>Parameters Tab:</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Time Step</td>
<td>Simulation time step, in sec.</td>
</tr>
<tr>
<td>Total Time</td>
<td>Total simulation time, in sec.</td>
</tr>
<tr>
<td>Free Run checkbox</td>
<td>When the Free Run checkbox is not checked, the simulation will run up to the Total Time and then stop. But when it is checked, the simulation will run in the free-run mode and it will keep on running until manually stopped. In the free-run mode, voltage/current scopes can be used to monitor and display voltages and currents in the middle of the simulation.</td>
</tr>
<tr>
<td>Print Time</td>
<td>Time from which simulation results are saved to the output file. No output is saved before this time.</td>
</tr>
<tr>
<td>Print Step</td>
<td>Print step. If it is set to 1, for example, every data point will be saved to the output file. If it is set to 10, only one out of 10 data points will be saved. This helps to reduce the output file size.</td>
</tr>
<tr>
<td>Load Flag</td>
<td>Flag for the LOAD function. If the flag is 1, the previous simulation values (saved by setting the Save Flag) will be loaded from a file (with the “.ssf” extension) as the initial conditions.</td>
</tr>
<tr>
<td>Save Flag</td>
<td>Flag for the SAVE function. If the flag is 1, values at the end of the current simulation will be saved to a file with the “.ssf” extension.</td>
</tr>
</tbody>
</table>

In PSIM, the simulation time step is fixed throughout the simulation. In order to ensure accurate simulation results, the time step must be chosen properly. The factors that limit the time step in a circuit include the switching period, widths of pulses or waveforms, and intervals of transients. It is recommended that the time step should be at least one magnitude smaller than the smallest of the above.
Also, an interpolation technique is implemented which will calculate the switching instants more accurately. With this technique, the error due to the misalignment of switching instants and discrete simulation points is significantly reduced. It is possible to simulate with a large time step while still maintaining accurate results.

The allowable maximum time step is automatically calculated in PSIM. It is compared with the time step set by the user, and the smaller value of the two will be used in the simulation.

With the SAVE and LOAD functions, the circuit voltages, currents and other quantities can be saved at the end of a simulation session, and loaded back as the initial conditions for the next simulation session. This provides the flexibility of running a long simulation in several shorter stages with different time steps and parameters. Components values and parameters of the circuit can be changed from one simulation session to the other. The circuit topology, however, must remain the same.

**SimCoder Tab**

<table>
<thead>
<tr>
<th>Hardware Target</th>
<th>The hardware target can be one of the following:</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td><em>None</em>: No hardware target in the circuit</td>
</tr>
<tr>
<td></td>
<td><em>F2833x</em>: F2833x Hardware Target for TI F2833x series DSP</td>
</tr>
<tr>
<td></td>
<td><em>F2803x</em>: F2803x Hardware Target for TI F2803x series DSP</td>
</tr>
<tr>
<td></td>
<td><em>PE-Pro/F28335</em>: PE-Pro/F28335 Hardware Target</td>
</tr>
<tr>
<td></td>
<td><em>PE_Expert3</em>: PE-Expert3 Hardware Target</td>
</tr>
<tr>
<td></td>
<td><em>KV3x</em>: KV3x Hardware Target for Freescale KV3x series MCU</td>
</tr>
<tr>
<td>Memory Map Options</td>
<td>Specify the memory map for compiler. For F2833x and F2803x hardware target:</td>
</tr>
<tr>
<td></td>
<td>RAM Debug;</td>
</tr>
<tr>
<td></td>
<td>RAM Release;</td>
</tr>
<tr>
<td></td>
<td>Flash Release; and</td>
</tr>
<tr>
<td></td>
<td>Flash RAM Release.</td>
</tr>
<tr>
<td></td>
<td>For PE_Expert3 hardware target:</td>
</tr>
<tr>
<td></td>
<td>PE-View9</td>
</tr>
<tr>
<td></td>
<td>PE-View8</td>
</tr>
<tr>
<td>CPU Version</td>
<td>Specify the CPU version.</td>
</tr>
<tr>
<td></td>
<td>For F2833x: F28335, F28334, and F28332.</td>
</tr>
<tr>
<td></td>
<td>For F2803x: F28035, F28034, F28033, F28032, F28031, and F28030</td>
</tr>
<tr>
<td>Default Data Type</td>
<td>This parameter is for fixed-point DSPs, such as F2803x. The default data type options are: Integer, IQ0, IQ1, ... IQ30.</td>
</tr>
<tr>
<td></td>
<td>If the box for Check Fixed-Point Range is checked, the SimCoder will check all the variables against the range and display the result.</td>
</tr>
<tr>
<td>DMC Library Version</td>
<td>SimCoder has function blocks of all the functions in TI's DMC library for the following DMC versions: 4.0, 4.1, and 4.2.</td>
</tr>
<tr>
<td>Comments</td>
<td>Comments can be entered and these comments will be inserted at the beginning of the automatically generated code.</td>
</tr>
</tbody>
</table>

### 1.7 Component Parameter Specification and Format

The parameter dialog window of each component in PSIM has three tabs: **Parameters, Other Info, and Color**, as shown below.
The parameters in the **Parameters** tab are used in the simulation. The information in the **Other Info** tab, on the other hand, is not used in the simulation. It is for reporting purposes only and will appear in the parts list in **View >> Element List** in PSIM. Information such as device rating, manufacturer, and part number can be stored under the **Other Info** tab.

The component color can be set in the **Color** tab.

Parameters under the **Parameters** tab can be a numerical value or a mathematical expression. A resistance, for example, can be specified in one of the following ways:

- 12.5
- 12.5k
- 12.5Ohm
- 12.5kOhm
- 25./2.0hm
- R1+R2
- R1*0.5+(Vo+0.7)/Io

where R1, R2, Vo, and Io are symbols defined either in a parameter file (see Section 4.1), or in a main circuit if this resistor is in a subcircuit (see Section 6.3.4.1).

Power-of-ten suffix letters are allowed in PSIM. The following suffix letters are supported:

- G: $10^9$
- M: $10^6$
- k or K: $10^3$
- m: $10^{-3}$
- u: $10^{-6}$
- n: $10^{-9}$
- p: $10^{-12}$

A mathematical expression can contain brackets and is not case sensitive. The following mathematical functions are allowed:

- +: addition
- -: subtraction
- *: multiplication
- /: division
- ^: to the power of [Example: $2^3 = 2*2*2$]
- SQRT: square-root function
- SIN: sine function
- COS: cosine function
- ASIN: sine inverse function
- ACOS: cosine inverse function
- TAN: tangent function
- ATAN: inverse tangent function
- ATAN2: inverse tangent function $[-\pi <= \text{atan2}(y,x) <= \pi]$
- SINH: hyperbolic sine function
- COSH: hyperbolic cosine function
- EXP: exponential (base e) [Example: $\text{EXP}(x) = e^x$]
- LOG: logarithmic function (base e) [Example: $\text{LOG}(x) = \ln(x)$]
- LOG10: logarithmic function (base 10)
- ABS: absolute function
- SIGN: sign function [Example: $\text{SIGN}(1.2) = 1$; $\text{SIGN}(-1.2)=-1$]
PSIM’s schematic program provides interactive and user-friendly interface for circuit schematic entry and editing. The PSIM user interface consists of an integrated set of windows, tools, menus, toolbars, and other elements that allow you to create, simulate, and refine your circuits in one places.

2.1 PSIM Environment

The following figure shows typical screen display of PSIM environment. In the figure, to illustrate as examples, two PSIM circuit files are open: a boost power factor correction circuit and a dc-dc buck converter circuit.

By default, the menu bar and the standard toolbar appear on top of the window, while the frequently used element bar appears at the bottom, and the Project View is on the left hand side.

On the right hand side is the Design window. This is a graphic editor where users can build and editor their simulation circuit schematics. User may arrange schematics in the Design window in tiles (as shown above), or in tabs (as shown below).
The Project View window provides an organized tree view of user’s projects and their related files, as well as the simulation result graphs. Each PSIM circuit is treated as a project. The following content are displayed in stacking tiers in the project view:

- **Project Name:** Usually this is the same as the top level PSIM circuit file name.
- **Documents:** Any files related to the project, for example document, datasheet, etc.
- **Study:** Name of the study
- **Schematic:** The PSIM schematic files, top level and subcircuits.
- **Graphs:** All probes in the PSIM schematic are included in the graph list.

The following shows a buck converter example in the Project View.

In this example, the project is the buck converter. It contains one study. The main circuit is "buck - main.psimsch", and the subcircuit is "buck - sub.psimsch". There are two simulation waveforms: I(S1.L1) and Vo.

After the simulation is done, the waveforms I(S1.L1) and Vo can be loaded into Simview by simply double
clicking on the waveform names in Project View. The waveforms can also be embedded into the schematic by dragging into the schematic. For example, the figure above shows the $V_o$ waveform embedded in the schematic.

A project may contain multiple studies. For example, one may study the buck converter circuit with a different load filter or switching frequency. To create another study out of an existing study, right click on the existing study "buck - main" and select **Create Study copy**. A dialog window will appear as shown below to allow you to define the new study name and determine if you wish to make a copy of the subcircuit.

In this example, we will create a new study called "buck - main1" and create a copy of the subcircuit. After confirmation, the new study is created as shown below. The new files "buck - main1.psimsch" and "buck - sub.psimsch" are placed in a newly created folder "buck - main\buck - main1".

To add an existing schematic file into the project as another study, right click on the project "buck - main" and select **Add Study**. To save the project, right click on the project "buck - main" and select **Save Project**.
2.2 Creating a Circuit

The basic and most commonly used functions provided for circuit creation are:

Get Element

There are several ways to get an element from the element library. One is to use the pull-down menu. Go to the **Elements** menu, and go into the submenu and highlight the element to be selected.

The most often used elements can be selected the **Element Toolbar**. It is located at the bottom of the PSIM screen by default.

Another way is to use the **Library Browser**, as shown below. The Library Browser provides a convenient way of navigating through the library. To launch the Library Browser, go to **View >> Library Browser**.

---

**Place**

Once an element is selected from the menu, the image of the element will appear on the screen and move with the mouse. Click the left button of the mouse to place the element at desired location on schematic.

**Select Element(s)**

To select an existing element on a schematic, click on the element. A rectangle will appear around the element. To select a section of a circuit, keep the left button of a mouse pressed and drag the mouse until the rectangle covers the selected area.

**Rotate**

Before the element is placed, right click to rotate the element. After an element is selected, select **Edit >> Rotate** to rotate the element.

**Wire**

To connect a wire between two nodes, select **Edit >> Wire**. The image of a pen will appear on the screen. To draw a wire, keep the left button of the mouse pressed and drag the mouse. A wire always starts from and end at a grid intersection.

For easy inspection, a floating node is displayed as a circle, and a junction node is displayed as a solid dot.

**Label**

If two or more nodes are connected to the same label, they are connected. It is equivalent as though they were connected by wire. Using labels will reduce the cross-wiring and improve the schematic layout.

The text of a label can be moved. To select the text, left click on the label, then press the **Tab** key.

**Assign**

To assign the parameters of an element, double click on the element. A dialog box will appear. Specify the values and hit the <Return> key or click on **OK**.
Move  To move an element or a circuit block, select the element/circuit block and drag the mouse while keeping the left button pressed.

Pan Schematic  To scroll schematic, right click and drag the mouse.

2.3 File Menu

The following functions are provided in the File menu for various file operations:

New  To create a new schematic with a single worksheet with no size limit.
New (worksheet)  To create a new schematic with a predefined worksheet size.
Open  To open an existing schematic file.
Open Examples  To open sample schematic files that come with PSIM.
Change Worksheet Size  To change the worksheet size.
New Project  To create a new PSIM project.
Open Project  To open an existing PSIM project.
Save Project  To save current PSIM project.
Close  To close the current schematic file.
Close All  To close all schematic files.
Save  To save the current schematic file.
Save As...  To save the current schematic file to a different name.
Save All  To save all schematic files.
Save with Password  To save a schematic file so that it is protected with a password. When a file is password protected, it can still be used in the simulation, but one needs to enter the correct password in order to see the schematic. The password protection is used in situations where the person who created the file needs to share it with someone else, but does not wish to reveal the details of the schematic.
Save in Package File  To save a schematic file and all associated files to one single package file. This is especially useful if the main circuit calls multiple subcircuits, and one needs to send the files to someone else. Rather than finding and collecting all the subcircuit files, one can just create the package file and send out the single package file.
Save as Older Versions  To save a file in the previous version format. Note that if the file uses elements that are unique in the current version, these elements will be omitted.
Print  To print the schematic. Note that the schematic is printed as it appears on the screen. If you zoom in or out the schematic, the printout will be changed accordingly.
Print Preview  To preview the printout.
Print Selected  To print only a portion of the schematic selected.
Print Selected Preview  To preview the printout of the portion of the schematic selected.
Print Page Setup  To adjust the print page position and set the print page legend.
Printer Setup  To set up the printer.
Exit  To exit the PSIM schematic program.

2.4 Edit Menu

The following functions are provided in the Edit menu for circuit editing:

Undo  To undo the previous change.
Redo  To go back to the state before undoing the changes.
Cut  To cut the selected circuit out of the schematic. The circuit that is cut can be pasted back.
To delete an element or a portion of the circuit, select the item and hit <Delete> key.
Copy  To copy an element or a portion of a circuit into a buffer, which can then be pasted back.
Paste  To paste back the copied element or circuit.
Select Matched Elements To select the elements which matches the specification.

Select All To select the entire schematic.

To select only a portion of the schematic, left click and drag the mouse.

Copy to Clipboard To copy the schematic image to the clipboard which can then be pasted back in another software. One can choose one of the three options: Metafile Format, Color Bitmap, or Black and White bitmap. The metafile format is vector based, and gives better image quality especially when the image is resized. The Black & White option will result in a smaller image file size as compared to the color bitmap.

Draw To draw images on the schematic for display purposes. The following images are provided: line, ellipse, rectangle, half-circles, bitmap images, and graph.

To draw a bitmap image: left click the mouse and drag the mouse to define the area that will contain the bitmap image. Then select the bitmap file.

To draw a graph, left click the mouse and drag the mouse to define the area that will display the waveform of selected probe.

Change All Text Font To change the font for all the text in the opened PSIM file

Change all Text Link Font To change the font for all the text link in the opened PSIM file.

Place Text To place text on the screen, choose Text. Enter the text in the dialog box, and click the left button of the mouse to place it.

Place Wire To enter the wiring mode. The cursor will change to the shape of a pen.

Place Label To place a label on the schematic. When two nodes are connected to two labels of the same name, they are considered physically connected.

Place External Port To place an external port

Edit Attributes When an element is selected, choose Attributes to bring out the property dialog window.

Add/Remove Current Scope To add or remove the current scope for an element that has the current flag. After this function is selected, click on top of the element, and select the branch current name to display the current scope. Select the branch current name again to remove the current scope.

Show/Hide Runtime Variables To show or hide the parameters of elements that can be changed at runtime in the middle of the simulation. After this is selected, the text of the parameter will appear. Double click on the text, and a small dialog window will appear. Enter the new value directly in the data field, and click Apply. Or alternatively, click on the up/down arrow keys on the keyboard to increase/decrease the value.

Disable To disable an element or part of a circuit. When the element or the circuit is disabled, it will be grayed out and will be treated as non-existent as far as the simulation is concerned. This function is useful if an element or circuit needs to be excluded but not deleted from the circuit.

Enable To enable a previously disabled element or circuit.

Rotate To rotate the selected element or a portion of the circuit by 90° clockwise.

Flip Left/Right To flip the selected element horizontally.

Flip Top/Bottom To flip the selected element vertically.

Find To find a particular element based on type and name.

Find Next To repeat the previous Find operation.

Find in Files To find a particular element in several files.

Edit Library To edit PSIM image libraries. For more details, please refer to Section 2.12.

Image Editor To launch the image editor. For more details, please refer to Section 2.13.

Escape Quit from any of the above editing modes by choosing Escape.

2.5 View Menu

The following additional functions are provided in the View menu for circuit editing:
Application Look To select the display style of the PSIM windows.
Status Bar To show/hide the status bar.
Toolbar To show/hide the toolbar.
Element Bar To show/hide the element bar.
Library Browser To launch the Library Browser. The Library Browser is another way of accessing the PSIM Element library.
Project View To launch the Project View. The project view organizes and manages the related files. The projects organizing structure has been illustrated in Section 2.1
Zoom In To zoom in the schematic.
Zoom Out To zoom out the schematic.
Fit to Page To adjust the zooming so that the entire schematic fits the screen.
Zoom In Selected To zoom in to the selected area.
Zoom Level To zoom the schematic to 10%, 20%, ..., 200%, and custom size.
Element List To generate the parts list of the circuit.
Element Count To count the number of elements. Voltage/current probes and meters are not included in the element count.
Display Voltage/Current If the option Save all voltages and currents (under Options >> Settings >> General) is checked, after the simulation is complete, choose this function to display any node voltages or branch currents.
Display Differential Voltage With the option Save all voltages and currents checked, after the simulation is complete, choose this function to display any voltages between two nodes.
Set Node Name With the option Save all voltages and currents checked, after the simulation is complete, choose this function to define the name of a node so that the displayed voltage waveform has the specified name.
Refresh To refresh the screen display.

2.6 Design Suites Menu

Functions are provided in the Design Suites menu to run two design suite templates which generate electrical circuit schematics automatically.

The following functions are provided:
Update Parameters To update the parameters in the circuit generated by design suite
Show Design File To display the system in design template form
Display Parameters To display the parameters of the system
HEV Design Suite To run the design templates in the HEV Design Suite. Four design templates are provided: HEV Powertrain System, PHEV (plug-in hybrid electric vehicle) Powertrain System, HEV Generator, and HEV Traction Motor. Each template has its linear and nonlinear version.
Motor Control Design Suite To run the design templates in the Motor Control Design Suite. Five design templates are provided: PMSM (IPM) Drive, PMSM(IPM) Drive (Nonlinear), PMSM(SPM) Drive, PMSM Drive, and Induction Motor Drive. For more information about how to use Motor Control Design Suite, refer to the document "Tutorial - Motor Control Design Suite.pdf".

2.7 Subcircuit Menu

Functions are provided in the Subcircuit menu for subcircuit editing and manipulation.

The following functions are to be performed in the parent circuit (outside the subcircuit):
New Subcircuit To create a new subcircuit
Load Subcircuit To load an existing subcircuit. The subcircuit will appear on the screen as a block.
Edit Subcircuit  To edit the size and file name of the subcircuit
Display Subcircuit Name  To display the name of a selected subcircuit in the main circuit
Show Subcircuit Ports  To display the port names of the subcircuit in the main circuit
Hide Subcircuit Ports  To hide the port names of the subcircuit in the main circuit
Subcircuit List  To list the file names of the main circuit and the subcircuits

The following functions are to be performed inside the subcircuit:

Set Size  To set the size of the subcircuit
Place Bi-directional Port  To place a bi-directional connection port in the subcircuit
Place Input Signal Port  To place an input signal connection port in the subcircuit
Place Output Signal Port  To place an output signal connection port in the subcircuit
Display Port  To display the connection port of the subcircuit
Edit Default Variable List  To edit the default variable list of the subcircuit. This is done inside the subcircuit.
Edit Image  To edit the subcircuit image
One Page up  To go back to the main circuit. The subcircuit is automatically saved.
Top Page  To jump from a lower-level subcircuit to the top-level main circuit. This is useful for circuits with multiple layers of subcircuits.

If the functions Set Size, Display Port, Edit Default Variable List, and Edit Image are performed in the main circuit, they will be applied to the main circuit instead.

There are three types of subcircuit ports for signal interface with the main circuit: Bi-directional port for power circuit and mechanical systems, and input signal and output signal ports for control circuit.

Even though bi-directional ports also work for control circuit, it is strongly recommended to use input or output signal ports for control circuit for better clarity. Furthermore, if a subcircuit is involved in code generation, only input or output signal ports can be used.

Right click on top of the subcircuit block, and choose Attributes to display the subcircuit property dialog window. There are three tabs: Subcircuit Info, Subcircuit Variables, and Color.

In the Subcircuit Info Tab:

In this tab, the name of the subcircuit can be edited. click on the Change Subcircuit File button to change to a different subcircuit. The selected subcircuit file will be loaded instead.

In the Subcircuit Variables Tab:

In this tab, variables used in the subcircuit can be edited. For example, a resistor in the circuit has the resistance defined as "Rparasitic", and for better clarity, this resistance is referred to as "Parasitic Resistance". Also, the resistance has a value of 1mOhm. This variable will be entered as:

Variable Description: Parasitic Resistance
Variable Name: Rparasitic
Variable Value: 1m

When the checkbox for "Parasitic Resistance" is checked, in the main circuit, this variable will be displayed as:

Parasitic Resistance = 1m

Since subcircuit variable list can be edited, the current variable list may be different from the default variable list. One can click on the Set as Default Variables button to set the current variable list as the default list, or click on the Reload Default Variables button to reload the default list if the default list has been modified.

Two functions are provided at the bottom of the dialog for SimCoder for automatic code generation. Click on
the Generate Code button to generate code for this subcircuit. If the checkbox Replace subcircuit with generated code for simulation is checked, the schematic inside the subcircuit will be replaced by the generated code for simulation.

In the Color Tab: In this tab, the subcircuit color can be changed.

Example: Use of Subcircuit

The circuit below illustrates the use of subcircuit. The circuit on the left is a buck converter, with the L-C filter inside a subcircuit. The content of the subcircuit is shown on the right.

In this example, there are two bi-directional ports ("in+" and "in-") on the left, and two bi-directional ports ("o+" and "o-") on the right.

<table>
<thead>
<tr>
<th>Subcircuit</th>
<th>Inside the subcircuit:</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1" alt="Subcircuit Diagram" /></td>
<td><img src="image2" alt="Inside Subcircuit Diagram" /></td>
</tr>
</tbody>
</table>

**2.7.1 Creating Subcircuit - In the Main Circuit**

The following are the steps to create the subcircuit “chop_sub.sch” in the main circuit “chop.sch”.

- Open or create the main circuit “chop.sch”.
- If the file “chop_sub.sch” does not exist, go to the Subcircuit menu, and select New Subcircuit. If the file exists, select Load Subcircuit instead.
- A subcircuit block (rectangle) will appear on the screen. Place the subcircuit.

If the circuit that is to be converted into a subcircuit has already been created in the main circuit, a quick way of converting it into a subcircuit is to select the circuit, and then right click and choose Create Subcircuit. Specify the subcircuit file name as "chop_sub.sch", and the circuit will be converted into a subcircuit. Adjust the port location and wire connection if necessary.

**2.7.2 Creating Subcircuit - Inside the Subcircuit**

To enter the subcircuit, double click on the subcircuit block.

- Create/edit the content of the subcircuit circuit exactly the same way as in the main circuit.
- To specify the subcircuit size, select Set Size in the Subcircuit menu. In this example, the size is set to 4x7 (width of 4 divisions and height of 7 divisions). Note that the size of the subcircuit should be chosen such that it gives the proper appearance and allows easy wire connection in the main circuit.
- Once the subcircuit is complete, define ports to connect the subcircuit nodes with the corresponding nodes in the main circuit. Choosing Place Port in the Subcircuit menu, and a port image will appear.
After the port is placed in the circuit, a pop-up window (shown on the left below) will appear.

The diamonds on the four sides represent the connection nodes and the positions of the subcircuit. They correspond to the connection nodes of the subcircuit block on the right. There are no diamonds at the four corners since connections to the corners are not permitted.

When a diamond is selected, it is colored red. By default, the left diamond at the top is selected and marked with red color. Click on the desired diamond to select and to specify the port name.

In this example, in the main circuit “chop.sch”, there are four linking nodes, two on the left side and two on the right side of the subcircuit block. The relative position of the nodes are that the upper two nodes are 1 division below the top and the lower two nodes are 1 division above the bottom.

To specify the upper left linking node, click on the top diamond of the left side, and type “in+”. The text “in+” will be within that diamond box and a port labelled with “in+” will appear on the screen. Connect the port to the upper left node. The same procedure is repeated for the linking nodes “in-”, “out+”, and “out-”.

After the four nodes are placed, the node assignment and the subcircuit appear as shown below.

The creation of the subcircuit is now complete. Save the subcircuit, and go back to the main circuit.

2.7.3 Connecting Subcircuit - In the Main Circuit

Once the subcircuit is created and connection ports are defined, complete the connection to the subcircuit block in the main circuit.

- In the main circuit, the connection points on the borders of the subcircuit block appear as hollow circles.

- Select the subcircuit block, and select Show Subcircuit Ports in the Subcircuit menu to display the
port names as defined inside the subcircuit.
- Connect the wires to the connection points accordingly.

2.7.4 Other Features of the Subcircuit

This section describes other features of the subcircuit through the example shown below.

2.7.4.1 Passing Variables from the Main Circuit to Subcircuit

In this example, the main circuit “main.sch” uses a subcircuit “sub.sch”. In the subcircuit, the inductance value is defined as “L” and the capacitance is defined as “C”. The default values of L and C can be set by selecting Subcircuit | Set Default Variable List. In this case, L is set to 5mH and C is set to 100uF.

When the subcircuit is loaded into the main circuit the first time, this default variable list will appear in the tab “Subcircuit Variables” in Subcircuit | Edit Subcircuit from the main circuit “main.sch”. New variables can be added here and variable values can be changed. In this case, L is changed to 2mH, and C is kept the same as the default value.

Note that the variables and the values are saved to the netlist file and used in simulation. The default variable list inside the subcircuit is not saved to the netlist and is not used for simulation.

This feature allows the parameters of a subcircuit to be defined at the main circuit level. In the case where the same subcircuit is used several times in one main circuit, different parameters can be assigned to the same variable. For example, if the subcircuit “sub.sch” is used two times in above example, in one subcircuit L can be defined as 3mH, and in another subcircuit L can be defined as 1mH.

Note that this example also illustrates the feature that parameters can be defined as a variable (for example “Vin” for the input dc voltage source) or a mathematical expression (for example “R1+R2” for the load resistance). The variables “Vin”, “R1”, and “R2”, are defined in the parameter file “para-main.txt”. See Section 4.1 for more details.

2.7.4.2 Customizing the Subcircuit Image

The following are the procedures to customize the subcircuit image of “sub.sch”:
- In the subcircuit, select **Edit Image** in the **Subcircuit** menu. A window will pop-up, as shown below.

In the window, the diamonds marked red are the connection nodes of the subcircuit block, in exactly the same positions as appearing in the main circuit.

- Use the drawing tool to create/edit the image for the subcircuit block. If the drawing tool is not already displayed, go to the **View** menu and check **Drawing Tools**. Click on **Zoom In** and **Zoom Out** icons on the toolbar to adjust the size of the image working area.

After the image is created, the pop-out window will appear as follows.

- Go back to the subcircuit window (“sub.sch” in this case), and save the subcircuit. The new subcircuit block image should appear in the main circuit.

### 2.7.4.3 Including Subcircuits in the PSIM Element List

If you create a directory called “User Defined” under the PSIM directory, and place subcircuits inside this directory, subcircuits will appear as items in the **Elements** menu, under **Elements | User Defined**, just like any other PSIM elements. You can also create subdirectories under the directory **User Defined**, and place subcircuits inside the subdirectories. For example, the **Elements** menu may look like this:

- Power
- Control
- Other
- Sources
- Symbols
- User Defined
  - Subcircuit 1
  - Project A
    - Subcircuit 2
    - Subcircuit 3
In this way, common-used custom-built subcircuits can be grouped together and easily managed and accessed.

## 2.8 Elements Menu

In PSIM, all the elements are stored under the **Elements** menu. They are stored in the following menus:

- **Power**
  - Power circuit elements, such as R, L, C, switching devices, transformers, motor drive modules, and etc.

- **Control**
  - Control circuit elements, such as computational logic, digital control elements and etc.

- **Other**
  - Elements interconnecting power and control circuit, such as switch controllers, voltage/current sensors, probes, and etc.

- **Sources**
  - Various voltage and current sources.

- **Symbols**
  - Symbols for drawing purpose, not for simulation usage.

- **Event Control**
  - Event control elements

- **SimCoder**
  - SimCoder blocks for automatic code generation.

- **User Defined**
  - Users can create a subfolder called "User Defined" in the PSIM folder, and place common used files in this folder. The folder "User Defined" and files in the folder will appear in the **Elements >> User Defined** menu.

## 2.9 Running Simulation

There are two options to run PSIM simulation: using the Simulate Menu or with Command Line.

### 2.9.1 Simulate Menu

The following functions are provided in the **Simulate** menu for running simulation:

- **Simulation Control**
  - To set the simulation parameters such as time step, total time, etc. When this is selected, the cursor will change to the image of a clock. Place this clock on the schematic, and double click to display the property window.

- **Run Simulation**
  - To run the simulation.

- **Cancel Simulation**
  - To cancel the simulation that is currently in progress.

- **Pause Simulation**
  - To pause the simulation that is currently in progress.

- **Restart Simulation**
  - To resume a paused simulation.

- **Simulate Next Time Step**
  - To run the simulation to the next time step, and pause.

- **Run SIMVIEW**
  - To launch the waveform display program SIMVIEW.

- **Run MonteCarlo Simulation**
  - To run the Monte Carlo simulation

- **Run Parameter Sweep**
  - To run parameter sweep simulation

- **Generate Netlist File**
  - To generate the netlist file from the schematic.

- **Generate Netlist File (xml)**
  - To generate the netlist file in xml format from the schematic

- **View Netlist File**
  - To view the generated netlist file.

- **Show Warning**
  - To show the warning messages, if any, from the simulation.

- **Show Fixed-Point Range Check Result**
  - To display the fixed-point range check result.

- **Arrange SLINK Nodes**
  - To rearrange the SLINK nodes. This function is for the SimCoupler Module for co-simulation with Matlab/Simulink. Please refer to Section 3.6 for more details.

- **Generate Code**
  - To generate code from the control schematic. This function is for SimCoder for automatic code generation. Please refer to *SimCoder User Manual* for more details.

- **Open Generated Code Folder**
  - To open the folder where the generated code are located.

- **Runtime Graph**
  - To select waveforms to show in the middle of a simulation run.
To view the simulation results in the middle of the simulation, one can either go to Simulate >> Runtime Graphs to select the waveforms, or use the voltage/current scopes (under Elements >> Other >> Probes) to view the waveforms.

The difference between the runtime graphs and the voltage/current scopes is that only waveforms that are saved for display in SIMVIEW (such as voltage probes, current probes, current flags, etc.) are available for the runtime graphs. In addition, a runtime graph display the waveform in its entirety, from the beginning to the final study time. Because of this, the runtime graphs are disabled in the free-run mode as the final study time is undetermined.

On the other hand, voltage/current scopes can be used in either the one-time simulation mode or in the free-run mode. Voltage scopes can be connected to any nodes, and will display the node-to-ground voltage waveforms. On the other hand, current scopes are available to elements that have current flags (such as R-L-C branches and switches).

Moreover, in the free-run mode, the majority of the element parameters can be changed during runtime in the middle of the simulation. This makes it possible to tune a circuit while inspecting key waveforms using voltage/current scopes, until desired performance is achieved.

To illustrate how to run a simulation in the free-run mode, a buck converter circuit shown below is used as an example. The circuit on the left was originally set up for the one-time simulation, with the total simulation time set to a specific value.

To set up the simulation in the free-run mode:

- In Simulation Control, check the Free Run checkbox.
- Go to Elements >> Other >> Scopes, and select the 2-channel voltage scope. Connect the scope as shown above on the right.
- Double click on the scope, and the scope image will appear. Start the simulation, and the waveforms will appear and will be updated continuously in the scope. Change the scope settings as desired.
- Elements parameters can now be adjusted in the middle of the simulation. To adjust the gain of the PI controller, for example, right click on top of the PI block, and choose Runtime Variables >> Gain. The text of the gain "0.6" will be displayed if it has not been displayed already.
- Click on the text "0.6", and a small dialog window will appear. The screen should look as follows.

![Diagram](image)

- Place the cursor inside the input field of the dialog window for the gain, and change the gain either by pressing on the upper/down arrow keys on the keyboard, or by entering a new value and then clicking on **Apply**. Watch how the waveforms change as the gain is changed.

  Other parameters, such as current reference, dc input voltage, inductance, capacitance, and load resistance, can be changed in the similar way.

- Branch currents can also be displayed in the free-run mode. To display the inductor current, for example, right click on top of the inductor, and a menu will appear. Choose **Current Scopes** and the branch current name.

- An image of the current scope (similar to the voltage scope image, but without connection terminals) will appear. Double click on the scope to expand and view the inductor waveform.

Below is how the window would look like with both the voltage scope and the current scope.

Other branch currents, such as capacitor current, load current, diode current, or MOSFET switch current, can be displayed in the similar way.
2.9.2 Simulation Command-Line

Simulation can also be launched with the command line option by running the program PsimCmd.exe. For example, to simulate the circuit "buck.psimsch" which is stored in the folder "c:\Powersim\examples", go to the PSIM folder, and run the following command:

```
PsimCmd -i "c:\psim\examples\buck.psimsch" -o "c:\psim\examples\buck.smv"
```

The format of the command line is as follows:

```
PsimCmd -i "[input file]" -o "[output file]" -v "VarName1=VarValue1" -v "VarName2=VarValue2" -t "TotalTime" -s "TimeStep" -g
```

Note that the quotes around the parameter values must be present. The command-line parameters are:

- `-i`: Input schematic file name
- `-o`: Output file name (in either .txt or .smv extension)
- `-v`: Variable name and value. This parameter can be used multiple times. For example, to define the resistance R1 as 1.5 and the inductance L1 as 0.001, we have:
  
  `-v "R1=1.5"  -v "L1=0.001"
  `

- `-t`: Total time of the simulation
- `-s`: Time step of the simulation
- `-g`: Run SIMVIEW after the simulation is complete

Note that the number of variables that can be defined in a command line is limited to 30.

With the command-line option, one can run several circuits automatically in a batch run.

2.10 Options Menu

The following functions are provided in the Options menu for various settings:

**Settings**
To set the simulation parameters such as time step, total time, etc. When this is selected, the cursor will change to the image of a clock. Place this clock on the schematic, and double click to display the property window.

**Languages**
To select different languages for PSIM display.

**Auto-run SIMVIEW**
To automatically run SIMVIEW after the simulation is complete.

**Set Path**
To set the PSIM search paths and device file paths.
Enter Password  To enter the password to view a schematic file that is password protected.
Disable Password  To disable the protection of a schematic file that is password protected.
Customize...  To create customized toolbars, keyboard, and application menu frame.

Save Custom Settings...  To save the following custom settings to a file: Default element values; custom keyboard definition; and custom toolbar definition. This file can then be loaded on another computer using the Load Custom Settings... function. This is useful when you want to apply the same custom settings on another computer.

Load Custom Settings...  To load custom setting files saved by the Save Custom Settings... function. This will apply the custom settings defined in the file to this computer.
Load Legacy Tool Bars  To load legacy tool bars of previous PSIM versions.
Deactivate  To deactivate the PSIM license. This is for softkey version only.
Change Softkey Password  To change the password of login for running PSIM softkey version. This is for softkey version only.
Check for Software Update  To check if any newer software updates are available on the Powersim server. This is for licenses that have the Annual Software Maintenance only.

2.10.1 Setting Options

The Settings menu has tabs: General, Advanced, Colors, and Page Sizes.

The General tab contains these sections: Editing, Text Font, Printing, and Simulation:

In Editing section:
Display grid  Check this option to display the grid in the PSIM schematic.
Zoom factor  The zoom factor defined here is used when the schematic is zoomed in or out.
Enable rubber band  When checked, an element or a portion of a circuit remains connected with the rest of the circuit when moved.

Show print page border  When enabled, the border of the printout will be displayed.

In Text Font section:
Default text font  Set the default font for the text placed in the schematic.
Justification  Define how the text will be aligned.
Default graph font  Set the text font for the runtime graphs.

In Printing section:
Line thickness  Define the thickness of the line as it appears at the printout. It can be set to 1 (the thinnest) to 4 (the thickest). Note that the line thickness only affects the printout. It does not affect the display on the screen.

In Simulation Section:
Simulation result format  Simulation results can be saved in either binary format (default) or text format. The binary format will result in a smaller result file, and will be faster to load. Set the default font for the text placed in the schematic.
Output buffer size  When checked, the simulation data will be written to the result file in segment. For example, if the buffer size is set to 20 MB, the simulation data will be first saved to the buffer, and when it reaches 20 MB, the whole 20-MB data will be written to the result file. Please note that the runtime graph only plots the data in the buffer. Therefore, when the old data are saved to the file and the new data fills in the buffer, the runtime graph will only show the waveform of the new data, and the old waveform will be lost. To retain all the waveforms in the runtime graph, one can either increase the buffer size, or un-check this option.

When this option is un-checked, however, PSIM will allocate all the required memory for the buffer at the very beginning. If the simulation time step is small and the total time is long, and if there are many output curves, a very large memory may be required, which
will take some time to allocate, and may even fail if the computer does not have sufficient amount of memory.

**Disable simulation warning messages** When this option is checked, warning messages generated in the simulation are suppressed.

**Save all voltages and current** When this option is checked, all the voltages and currents of the circuit will be saved for display. To display a voltage or current, after the simulation is complete and after results are loaded into SIMVIEW, choose View >> **Display Voltage/Current** (or click on the corresponding icon). When the cursor is on top of a node or a branch, it will change to the image of a voltage probe or current clamp probe. Left click the mouse, and the corresponding voltage or current will appear in SIMVIEW.

To display a differential voltage, choose View >> **Display Differential Voltage**. Then click on the first node, and then the second node. The differential voltage waveform will appear in SIMVIEW.

**Maximum number of points for oscilloscope** It defines the maximum number of points that an oscilloscope will plot. Increase this number to display waveforms for a longer time interval.

The Advanced tab contains these sections: **Software Updates**, **Automatic Backup**, **Time-out**, **Code Generation Indication**, and **PSIM Help File**.

**In Software Updates section:**

**Check for software updates** When this option is checked, if you have the valid software annual maintenance, PSIM will automatically check for new updates on the Powersim server. If a new update is available, you will be prompted to install the update.

**On Automatic Backup:**

**Automatic backup** When this option is checked, PSIM will create a backup of the file currently being edited in the time interval specified. In case of a program crash, the backup file will preserve the previous work. The backup file is deleted automatically when the file is closed normally from the PSIM environment.

**In Time-Out section:**

**Idle time** When this option is checked, PSIM will be timed out after the program is idle for the specified amount of time. Note that this applies to the PSIM network version only.

When PSIM is timed out, the license will be released and other users will be able to check it out. When PSIM is back from the idle state, it will try to log back in the License Manager if a license is still available. If there is no license available, an error message will be posted.

This feature will prevent users from holding up licenses unintentionally.

**In Code Generation Indication section:**

**Show image next to elements** ... This is for SimCoder only for automatic code generation. When this option is checked, in the PSIM library, an image will appear next to the elements that can be used for code generation. This is used to differentiate elements that can be used for code generation from the ones that can not.

**In PSIM Help File section:**

**Use alternate PSIM help file path** By default, PSIM reads the help file psim.chm from the same PSIM folder. When this option is checked, PSIM will read the help file from the specified file path instead.

**Under the Colors tab:**

**Color settings** Colors for grids, elements, subcircuits, ports, wire, text, nodes, and labels can be set.

**Wire color** The wire color can be set either by default, or by circuit type.
2.10.2 Set Path Options

The Set Path... function in the Options menu allows users to define additional search paths when loading an external DLL file or device file. For example, if a schematic file uses a DLL file, and this DLL file is placed in a directory other than the schematic directory or the PSIM directory, this directory can be included in PSIM by using the Set Path function. Similarly, if a Thermal Module device is placed in a folder other than the default device folder, this device file can be used by PSIM schematic by including the folder in the Device File Path.

PSIM searches the DLL files in the following order:
- PSIM directory
- Schematic file directory
- Directories as defined in the PSIM Search Path section.

The first time that the DLL file is encountered, it will be loaded. For example, assume that the PSIM program files are in C:\PSIM, the schematic file is in C:\TEMP; and the directory as defined in the Set Path function is C:\TEMPDLL. The DLL file can be in one of the three places:
- C:\PSIM
- C:\TEMP
- C:\TEMPDLL

PSIM loads the Thermal Module device files in the following order:
- The "device" sub-folder in the PSIM directory
- Directories as defined in the Device File Path section.

All the device files in the PSIM’s device sub-folder and in the folders defined in the Device File Path will be loaded.

2.10.3 Customizing Toolbars and Keyboards

The procedures for create customized toolbars and to customize keyboards are described below.

Customizing Toolbars:

To create a toolbar called "new" and add the AND gate to the toolbar, for example, do the following:

- Choose View >> Custom Toolbars. The Custom Toolbars dialog window will appear. Choose New Toolbar, and the following window will appear.
- Specify the Toolbar Name as "new".
- Draw the AND gate icon in the icon editing area. Or if the icon is already available in the predefined icon images, select the icon and copy it to the icon editing area.
• Under the **Edit Command** section, with the option **Elements** selected, highlight "AND Gate". Then click on the **Add Button**. The icon will appear in the toolbar icon area. Click on **OK** to close the window, and go back to the Custom Toolbars window.

• Check "new" in the Custom Toolbars dialog window, and the new toolbar will appear. Uncheck the box will hide the toolbar.

**Customizing Keyboard:**

To define the key "r" for getting a resistor from the library, for example, do the following:

- Choose **View >> Custom Keyboard**. The Custom Toolbars dialog window will appear. Choose **New Toolbar**, and the following window will appear.
- In the section **Add Shortcut Key**, select the option **Elements**. Then find and highlight the element "Resistor".
- Move the cursor into the input field of **Press new shortcut key**, and press the key "r" on the keyboard. Then click on **Assign**.
- The key "r" will be assigned to the resistor, and the definition will appear in the **Current Shortcut Key** list.

### 2.11 Utilities Menu

Several utility programs are provided under the **Utilities** menu.

- **Parameter Tool**
  It launches a parameter file window. One can load an existing parameter file, or enter expressions for computation purposes.

- **s2z Converter**
  This program converts a s-domain function to a z-domain function. This program is part of the Digital Control Module option.

- **Device Database Editor**
  The device database editor PcdEditor.exe for the Thermal Module.

- **B-H Curve**
  This program plots the B-H curve of the saturable core element (under **Elements >> Power >> Magnetic Elements**).

- **Solar Module (physical model)**
  This program plots the i-v curve of the solar module (physical model) element (under **Elements >> Power >> Renewable Energy**). This function is part of the Renewable Energy option.

- **SimCoupler Setup**
  This will launch the program SetSimPath.exe that performs the setup for co-simulation between PSIM and Matlab/Simulink. This function is part of the SimCoupler Module.

- **Set Default PSIM Program**
  Run this function to set this version of PSIM to be the default program to open .psimsch, .sch, and .smv files when double clicking on these files in Windows Explorer.

- **DSP Oscilloscope**
  The DSP Oscilloscope function is available as part of the TI F2833x/F2803x Target. It is used together with the SCI functions to display DSP waveforms in real time. For more information on how to use the DSP Oscilloscope, please refer to the document "Tutorial - Using SCI for Real-Time Monitoring in TI F2833x Target.pdf".

- **Ultra-capacitor Model Tool**
  The parameter extraction tool for ultra-capacitor models. For more information, please refer to the document "Tutorial - Ultra-capacitor Model.pdf".
Launch/Export to SmartCtrl
To launch the SmartCtrl software, or if the ac sweep result is available, to export the ac sweep result to SmartCtrl. SmartCtrl is a separate software for control loop design. For more information, please refer to the Help menu in SmartCtrl.

Unit Converter
This program performs unit conversion in length, area, weight, and temperature.

Calculator
This will launch the Windows’ calculator.

2.12 Managing the PSIM Library

A PSIM library element consists of two parts: the netlist part and the image part. The netlist part comes from the netlist library, and there is only one netlist library, psim.lib. The netlist library can not be edited.

The image part comes from an image library. There can be multiple image libraries, and all the image libraries in the PSIM directory will be automatically loaded into PSIM. The standard image library provided by PSIM is psimimage.lib. This file also can not be edited. However, in order to facilitate users to copy images from the standard image library, the standard image library can be viewed by going to Edit >> Edit Library >> Edit library files, and choosing psimimage.lib.

Users can create their own custom image libraries. To create a new custom image library, go to Edit >> Edit Library >> Edit library files, and click on New library. Then define the library name as it appears in the PSIM Elements menu, and the library file name. This library file will be created and placed in the PSIM directory.

To edit an image library, go to Edit >> Edit Library >> Edit library files, and select the library file. The figure below shows the library editor dialog window. The dialog shows the menu tree of the library as well as various functions.

To create a new element in the custom image library, click on New Element, and select the netlist that this element corresponds to from the list. For example, the netlist name of the resistor is "R". To create a new element called "My Resistor", select the netlist "R". To create the image for this resistor, click on Edit Image.

The following functions are provided in the library editor:

- Up
  To move an element up in the menu
- Down
  To move an element down in the menu
- --->
  To move an element one level lower in the menu
- <---
  To move an element one level higher in the menu
- Add Separator
  To add a separator between elements
- Add Submenu
  To add a submenu in the library
2.12.1 Creating a Secondary Image

It is possible that some users may find certain element images in the standard PSIM image library psimimage.lib different from what they are used to use. In this case, users can create their own secondary images.

A secondary image can be created for an element in either standard image library psimimage.lib or users’ own custom image libraries. Secondary images are saved in a secondary image library with the .lib2 extension.

To illustrate the process, a secondary image will be created in the library "mylib.lib2" for the "Diode" element in the standard image library.

• Go to Edit >> Edit Library >> Edit secondary image library files, and click on New library. In the dialog, define the secondary image library name as "mylib.lib2".

• Then select "mylib.lib2" and click on Edit selected library. The dialog window for editing secondary image library will appear.

• Click on the Add button. From the PSIM library tree, navigate to Power >> Switches, and select "Diode". The element "Diode" will appear in the list of the secondary images. The text "PSIMIMAGE" in front of the "Diode" text shows that this is for the diode element in the standard image library psimimage.lib.

• Highlight "Diode", and click on the Edit button to create the image.

• If this image is to be used as the default image for this element, click on the "Set as Default Image".

After the secondary image is created, this image will be available for selection in the PSIM schematic. For example, if a diode is placed on the schematic, double click to display the property dialog of the diode, then click on the Color tab. Click on the pull-down arrow, and two images will be displayed. One from the standard image library, and the other from the custom image library mylib.lib.

If the secondary image is selected, all the images of the same element will be automatically changed to the secondary image. The selected image will also be set as the default image when a schematic is created or loaded the next time.
To share the secondary images that one creates with other people, one just has to send to them the secondary image library file (with the .lib2 extension).

### 2.12.2 Adding a New Subcircuit Element into the Library

There are two ways to add a custom model to the PSIM library list. One is to have the model in the form of a subcircuit, and then place the schematic file in a folder called user defined in the PSIM directory, or in one of the sub-folders of the user defined folder. Any schematic files and sub-folders under the user defined folder will appear in the PSIM library list.

Another way is to add the custom model directly to an image library. The advantage of this approach is that the custom element will have the same look-and-feel as the standard PSIM elements, giving it a better interface. It is also possible to associate a help file to the custom model.

There are three main steps to add a new element, modeled in a subcircuit, into the library:

- Create the subcircuit model of the new element.
- Add this element to the PSIM library.
- Create an on-line help file for this new element.

To illustrate this process, a LC-filter element is used as an example.

#### Step 1: Create Subcircuit

The first step is to create the subcircuit of the new element in the same way as if the subcircuit is to be called by another circuit. For example, the subcircuit of the 2nd-order LC filter, called "LC_filter.sch", and its image are shown below:

![Subcircuit Image](image)

In this case, the inductance and capacitance values will be defined through the interface, and need to appear in the property window of the new LC filter element. Therefore, the parameter value for the inductance needs to be defined as a variable, in this case, $L$, and the value for the capacitance as $C$.

Then from **Subcircuit >> Edit Default Variable List**, add the variables $L$ and $C$ as the default variables. This step is necessary as the new element obtains the parameter information from the default variable list. The
default variable list window should appear as follows.

Here **Variable Label** is the text that describes the parameter, **Variable Name** is the variable that is used as the parameter value in the subcircuit, and **Variable Value** is the default value of the parameter. In the example, for the inductor \( L \), the **Variable Label** is *Inductance*, the **Variable Name** is \( L \), and the **Variable Value** is 1m. For the capacitor \( C \), the **Variable Label** is *Capacitance*, the **Variable Name** is \( C \), and the **Variable Value** is 100u.

After the file is created, place it in the "lib" sub-folder in the PSIM directory.

**Step 2: Add the New Element to the PSIM Library:**

To add the subcircuit element into the PSIM library, follow these steps:

- Go to **Edit >> Edit Library >> Edit Library Files**, and choose the custom image library for the new element. Click on **New Library** to create a new image library, or select an existing library and click on **Edit Selected Library**.
- In the Library Editor, click on the button **New Element (Subcircuit)**. Enter the information to the dialog window as shown below:

![Subcircuit Element Dialog](image)

**Name:** Name of the new element as it appears in the PSIM library  
**Description:** Description of the new element  
**File Path:** The location of the subcircuit schematic file "LC_filter.sch". The schematic file of the subcircuit must be placed in the "lib" sub-folder in the PSIM directory.  
**Input nodes:** Number of input nodes.  
**Output nodes:** Number of output nodes.  
**Hide (menu):** Leave this box unchecked. If this box is checked, this element will not appear in the library.  
**Help File:** On-line help file associated with this element. This file must be placed in the "help" sub-folder in the PSIM directory. When the Help button is clicked in the property dialog window, this file will be displayed. This file can be a text file (which can be opened by a text editor such as NotePad) or a HTML file.

- Click on the buttons **Save Image Library** and **Update Menu**. The new element will appear in the library and will be ready to use.

### 2.12.3 Adding a New DLL Element into the Library

Similar to that of a subcircuit element, there are three main steps to add a new element, modeled in a DLL, into the PSIM library:

- Create the model in the DLL file.  
- Add this element to the PSIM library.  
- Create an on-line help file for this new element.

To illustrate this process, an inductor is used as an example.

**Creating the DLL:**
The first step is to create the inductance model in DLL. Please refer to the relevant section on how to create a custom DLL.

Here we assume that the DLL file, "inductor_model.dll", has already been created. It has one parameter called "Inductance", and two connecting nodes. The file is placed in the "lib" sub-folder in the PSIM directory.

**Adding the New Element to the PSIM Library:**

To add the DLL element into the PSIM library, follow these steps:

- Go to Edit >> Edit Library >> Edit Library Files, and choose the library for the new element. Click on New Library to create a new image library, or select an existing library and click on Edit Selected Library.

- In the Library Editor, click on the button New DLL File. Enter the information to the dialog window as shown below:

  ![DLL File Element dialog](image)

  **Name**: Name of the new inductor element as it appears in the PSIM library  
  **Description**: Description of the new inductor element  
  **File Path**: The location of the DLL file "inductor_model.dll" that models the new inductor element. The DLL file must be placed in the "lib" sub-folder in the PSIM directory.  
  **Input Nodes**: Number of input terminals of the new element.  
  **Output Nodes**: Number of output terminals of the new element.  
  **Hide (menu)**: Leave this box unchecked. If this box is checked, this element will not appear in the library.  
  **Help File**: On-line help file associated with this element. This file must be placed in the "help" sub-folder in the PSIM directory. When the Help button is clicked in the property dialog window, this file will be displayed. This file can be a text file (which can be opened by a text editor such as NotePad) or a HTML file.

- In the next dialog window, set the new element size as: Width = 5, and Height = 2. Then create an image for this element, or accept the default image.

- Click on the buttons Save Image Library and Update Menu. The new element will appear in the library and will be ready to use.

The information regarding the number of parameters and the parameter description for the new inductor element is obtained from the DLL file automatically. In this case, the new element will have one parameter as "Inductance".

### 2.13 Creating a Symbol Library

With the Image Editor in the Edit menu, one can easily create good component images very quickly. These images can be used as secondary images of PSIM library elements, or images of subcircuits. One can also store these images in a symbol library for the purpose of circuit wiring diagrams. Note that such a schematic is solely for display purposes, and can not be simulated.
The figure below shows a hardware circuit diagram from a SPI A/D converter example.

The blocks F28335, 74HCT138, and TLV1548 are all created by the Image Editor.

To illustrate how to create an image using the Image Editor, and save the image as a symbol into a custom library, we will create the image for the decoder 74HCT138 as shown below:

- In PSIM, create a new schematic window. Then choose Edit >> Image Editor. A rectangle will appear. Place the rectangle on the schematic, and press the Esc key to escape.

- Double click on the rectangle, and a dialog window will appear. In the Main tab, enter the data field as shown on the screen below. The Library Part Name is the name of the element as it appears in the library. The size of the block is 5 in width and 9 in height, without taking into account the length of the leads.

- Click on the Pins tab. In this tab, the connection pins will be defined. Click on the Add button, and define Location as "1 - Left", Name as "A", and Number as "1". Leave the boxes for Dot, clk, and Overline unchecked.

  If the boxes are checked, for Dot, there will be a circle between the connection pin and the block; for clk, a symbol > will be added inside the block to indicate that it is a clock; and for Overline, an overline will be added to the name.
• Click on the Add button, and define Location as "2 - Left", Name as "B", and Number as "2". Repeat the same process for the rest of the pins. The dialog windows below show the definitions of all the connection pins.

• Once all the pins are added, go back to the Main tab. Click on Save in library, and select [New Library]. Enter the library name as "My Symbol", and specify the library file name as "My Symbol". The library "My Symbol" will appear under the Elements menu, and this library will contain the newly created element 74HCT138.
SIMVIEW is PSIM’s waveform display and post-processing program. The following shows simulation waveforms in the SIMVIEW environment.

SIMVIEW reads data in either ASCII text format or SIMVIEW binary format. The following shows a sample text data file:

<table>
<thead>
<tr>
<th>Time</th>
<th>Isa</th>
<th>Isc</th>
<th>Isb</th>
<th>Tem_IM</th>
</tr>
</thead>
<tbody>
<tr>
<td>5.00E-06</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>7.14E-048</td>
</tr>
<tr>
<td>1.00E-05</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>1.08E-046</td>
</tr>
<tr>
<td>1.50E-05</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>0.000000000E+00</td>
<td>5.40E-046</td>
</tr>
<tr>
<td>2.00E-05</td>
<td>1.13E+00</td>
<td>-2.28E+00</td>
<td>1.13E+00</td>
<td>1.61E+017</td>
</tr>
<tr>
<td>2.50E-05</td>
<td>5.07E+01</td>
<td>-1.01E+01</td>
<td>5.07E+01</td>
<td>3.59E+015</td>
</tr>
</tbody>
</table>

Functions in each menu are explained in the following sections.

### 3.1 File Menu

The **File Menu** has the following functions:

- **Open**: Load a data file in ASCII text format (with .txt extension) or SIMVIEW binary format (with .smv extension)
- **Merge**: Merge another data file with the existing data file for display
- **Re-Load Data**: Re-load data from the same text file
- **Save As**: Save the waveforms to either binary data format or text format. When saving to the binary format, the current settings are also saved. In the FFT display, this will save the FFT results to a text file specified by the user.
- **Print**: Print the waveforms
- **Print Setup**: Set up the printer
- **Print Page Setup**: Set up the hardcopy printout size
- **Print Preview**: Preview the printout
- **Exit**: Quit SIMVIEW
When the data of a file are currently being displayed, if new data is available, by selecting **Re-Load Data**, new data will be loaded and waveforms will be re-drawn.

With the **Merge** function, data from multiple files can be merged together for display. For example, if one file contains the curves “I1” and “I2”, and another file contains the curves “V1” and “V2”, all four curves can be merged and displayed on one screen. If the second file also contains a curve with the same name “I1”, it will be modified to “I1_{\{second\_file\_name\}}” automatically where *second_file_name* is the name of the second file.

### 3.2 Edit Menu

The **Edit Menu** has the following functions:

- **Undo**: Go back to the previous X and Y axis settings
- **Copy to Clipboard**: Copy the waveforms to the clipboard either in metafile format or bitmap format.
- **View Data Points**: View the data points of the waveforms within the displayed range in a separate window. In this window, one can use the left mouse to highlight data points in rows or columns, then right mouse click and choose **Copy Selected** to copy the data to the clipboard. One could also just copy the row that the cursor is on by selecting **Copy Row**, or copy the entire data by selecting **Copy All**. One can then paste the copied data back in another program.

Note that the **Copy to Clipboard** function will copy the displayed waveforms on the screen to the clipboard. To save the memory and have the waveform image in black & white, first go to **Option** and de-select **Color** to have a black & white display, then copy the waveform to the clipboard.

### 3.3 Axis Menu

The **Axis Menu** has the following functions:

- **X Axis**: Change the settings of the X axis
- **Y Axis**: Change the settings of the Y axis
- **Choose X-Axis Variable**: By default, the first column of the data is selected as the X axis. However, other columns can also be selected as the X axis through this function.

The dialog box of the X/Y axis settings are shown below.

If the **Auto-Grid** box is checked, the number of axis divisions will be automatically determined. The data range and grid division, however, can be manually set.

The following figure shows a sine waveform is chosen as the X-axis versus a cosine waveform in the Y axis.
3.4 Screen Menu

The Screen Menu has the following functions:
- **Add/Delete Curves**: Add or delete curves from the selected screen
- **Add Screen**: Add a new screen
- **Delete Screen**: Delete the selected screen

A screen is selected by clicking the left mouse on top of the screen.

The property dialog window of curves is shown below.

![Property Dialog Window](image)

All the data variables available for display are in the *Variables Available* box, and the variables currently being displayed are in the *Variables for Display* box. After a variable is highlighted in the *Variables Available* box, it can be added to the *Variables for Display* box by clicking on “Add ->”. Similarly, a variable can be removed from display by highlighting the variable and clicking on “<- Remove”.

In the Edit Box, mathematical expressions can be specified. The mathematical expressions may contain brackets and are not case sensitive. The following math functions are allowed:

- **+**: addition
- **-**: subtraction
- *****: multiplication
- **/**: division
- **^**: to the power of [Example: \(2^3 = 2*2*2\)]
- **SQRT**: square-root function
- **SIN**: sine function
- **COS**: cosine function
- **TAN**: tangent function
- **ATAN**: inverse tangent function
- **EXP**: exponential (base e) [Example: \(\text{EXP}(x) = e^x\)]
- **LOG**: logarithmic function (base e) [Example: \(\text{LOG}(x) = \ln(x)\)]
- **LOG10**: logarithmic function (base 10)
- **ABS**: absolute function
- **SIGN**: sign function [Example: \(\text{SIGN}(1.2) = 1; \text{SIGN}(-1.2) = -1\)]
- **AVG**: moving average function that calculates the average of the curve up to the measured point.
- **AVGX**: periodic average function \(\text{AVGX}(y, T_p)\) where \(y\) is the curve name and \(T_p\) is the time interval where the average is calculated. Calculates the average of the curve \(y\) in each time segment with interval of the time segment as \(T_p\). For example, \(\text{AVGX}(V1, 0.016667)\) will calculate the average of the curve \(V1\) at the 60-Hz interval.
- **INT**: integration function

Type an expression in the Edit Box and click the "**Add ->**" button to add the calculated curve to the screen. Highlight the expression on the right and click the "<- **Remove**" button, the expression will be moved into the
Edit Box for further editing.

In the **Curves** tab, the curve properties, such as color, line thickness, marker symbol, and label, can be defined. A dialog window is shown below.

![Curves Tab](image)

The default settings of the curve color, line thickness, and mark symbol are defined in **Options** >> **Options**. In the **Screen** tab, the screen properties, such as foreground/background colors, grid color, and font size/type, can be defined. A dialog window is shown below.

![Screen Tab](image)

### 3.5 Measure Menu

The **Measure Menu** has the following functions:

- **Measure** Enter the measure mode.
- **Mark Data Point** Mark the x and y coordinate values of the data point in a selected curve
Max  Find the global maximum of a selected curve
Min  Find the global minimum of a selected curve
Next Max  Find the next local maximum of a selected curve
Next Min  Find the next local minimum of a selected curve

The Measure function allows the measurement of waveforms. After Measure is selected, the measure dialog window will appear. By clicking the left mouse, a line will appear and the values of the waveforms will be displayed. By clicking the right mouse, another line will appear and the different between the current position and the previous position, which is marked by the left mouse, will be measured. A SIMVIEW window with the measure dialog windows in these two modes are shown below.

Once Measure is selected, an individual curve can be selected by clicking on the pull-down menu on the Measure toolbar. The functions, Max, Min, Next Max, Next Min, Avg, and rms, can be used to evaluate the curve. Note that these functions are only enabled in the Measure mode.

3.6 Analysis Menu

The Analysis Menu has the following functions:

Perform FFT  Perform the FFT (Fast Fourier Transform) analysis of time-domain waveforms
Display in Time Domain  Show the corresponding time-domain waveforms of FFT results
Avg  Calculate the average value
Avg(|x|)  Calculate the average of the absolute value
RMS  Calculate the rms value
PF (power factor)  Calculate the power factor of two waveforms on the screen. The screen must display two curves only. Assuming the first curve is a voltage and the second curve is a current, the power factor is defined as the real power P divided by the apparent power S produced by the voltage and current.

Note that the power factor is different from the displacement power factor, defined as cos(\theta) where \theta is the angle difference between the fundamental components of the voltage and current. When the voltage and current are pure sine waves without harmonics, the power factor is the same as the displacement power factor.

P (real power)  Calculate the real power of two waveforms on the screen. The screen must display two curves only.
S (apparent power)  Calculate the apparent power of two waveforms on the screen. The screen must display two curves only.
THD  Calculate the THD (total harmonic distortion)
All these functions apply to the time interval currently being displayed on the screen.

By selecting **Perform FFT**, the harmonic spectrum (both the amplitudes and angle) of the time-domain waveforms can be calculated and displayed. To display the angles of the FFT results, double click on top of the screen (or click on the **Add/Delete Curves** icon). In the **Select Curves** tab, click on the **Angle** tab, and select the angles. The name convention of angles is \( \text{Angle}(D)_{\{\text{name}\}} \) for the angle in deg., and \( \text{Angle}(R)_{\{\text{name}\}} \) for the angle in rad., and \text{name} is the curve name in the time domain.

Note that, in order to obtain correct FFT results, the simulation must reach the steady state, and the data range must be restricted (using the manual range setting in the **X Axis** function) to have the integer number of the fundamental period. For example, for a 60-Hz fundamental frequency, the data length in display must be integer multiples of 1/60 sec.

### 3.7 View Menu

The **View Menu** has the following functions:

- **Zoom**: Zoom into a selected region
- **Re-Draw**: Re-draw the waveform using the auto-scale
- **Escape**: Escape from the Zoom or Measure mode
- **Standard Toolbar**: Enable/disable standard toolbar
- **Measure Toolbar**: Enable/disable measure toolbar
- **Status Bar**: Enable/disable status bar
- **Calculator**: Launch the Calculator in Simview

The interface of the calculator is shown below.

One key feature of the calculator is that it provides 9 memory spaces. By double clicking on a number in the Measure dialog window in Simview, the value will be automatically transferred to the calculator and stored in one of the memory spaces, starting from the top. In this way, data can be directly transferred to this calculator for calculation without the need to record them on a piece of paper.

### 3.8 Option Menu

The **Option Menu** has the following functions:

- **Options...**: Various options can be set here.
- **Grid**: Enable or disable the grid display
- **Color**: Set the curves to be either Color (default) or Black and White
The **Options** dialog window is shown below.

![Options dialog window](image)

Default curve settings, such as colors, line thickness, and mark symbols, are defined. Also, default text settings, such as font size, color are defined.

If the option **Redraw x-axis when loading new data** is checked, the waveform will be redrawn with the new x-axis range when new data is loaded. If this option is not checked, the x-axis range will be unchanged.

If the option **Engineering Unit** is checked, in the Measure dialog window, curve values will be displayed in engineering unit with suffix such as u, m, k, M (for example, 12.3456u). If this option is not checked, the values will be displayed in scientific unit (for example, 1.23456e-5). The value of **Significant Digits** defines the number of digits after the decimal points.

Also, the right mouse action can be set to either **Show menu**, **Pan**, or **Zoom**.

### 3.9 Label Menu

The **Label Menu** has the following functions:

- **Text**: Place text on the screen
- **Line**: Draw a line
- **Dotted Line**: Draw a dotted line
- **Arrow**: Draw a line with arrow

To draw a line, first select **Line** from the Label menu. Then click the left mouse at the position where the line begins, and drag the mouse while keeping the left button pressed. Dotted lines and lines with arrows are drawn in the same way.

If one is in the Zoom or Measure mode, and wishes to edit a text or a label, one should first escape from the Zoom/Measure mode by selecting “Escape” in the “View” menu.

### 3.10 Settings Menu

The **Settings Menu** has the following functions:

- **Re-Load Settings**: Re-load the settings from the .ini file and apply to the current display
- **Save Settings**: Save the current settings to a file with the same file name but with the .ini extension
- **Save Temporary Settings**: Save the current settings temporarily. The temporary settings are not saved to any files, and are discarded when the document is closed.
- **Load Temporary Settings**: Load the temporary settings and apply to the current display
- **Add to Favorites**: Save the current settings as a favorite. When saving a favorite, one can choose to save the following settings: line color and thickness, text font, Log/dB/FFT display settings, and x and y axis ranges.
- **Manage Favorites**: Manage the favorites

When Simview loads a data file (.txt or .smv file), if the corresponding .ini file exists, it will load the settings in
The functions *Load Temporary Settings* and *Save Temporary Settings* are used in situations where one wants to save the settings temporarily and uses it shortly after. For example, when comparing one waveform with another, one can first save the temporary settings when displaying the first waveform. Then display the second waveform and load the temporary settings.

Favorites are a convenient way of storing particular graph settings to be used later. For example, assume that Simview shows two screens, with the top screen displaying V1 in the red color and with certain x-axis and y-axis ranges, and the bottom screen displaying V2 in the blue color with its own y-axis range. If this settings is likely to be used again in the future, the settings can be saved as a favorite and used later.

To apply a favorite to the current display, go to the Settings menu and choose the favorite from the list. Note that when applying the favorite, the number of screens currently on display must be the same as the number of screen in the favorite.

### 3.11 Exporting Data

FFT results can be saved to a text file. Both simulation results (*.txt) and FFT results (*.fft) are in text format and can be edited using a text editor (such as Microsoft NotePad), or exported to other software (such as Microsoft Excel).

For example, to load a simulate result file “chop-1q.txt” in Microsoft Excel, follow these steps:

- In Microsoft Excel, select **Open** from the File menu. Open the file “chop-1q.txt”.
- In the dialog window **“Text Import Wizard - Step 1 of 3”**, under **Original data type**, choose **Delimited**. Click on **Next**.
- In the dialog window **“Text Import Wizard - Step 2 of 3”**, under **Delimiters**, choose **Space**. Click on **Next**.
- In the dialog window **“Text Import Wizard - Step 3 of 3”**, under **Column data format**, choose **General**. Click on **Finish**.
The following chapters provide the detailed information of the PSIM library elements. This chapter focuses on the Power circuit components.

4.1 Resistor-Inductor-Capacitor Branches

PSIM provides several combinations of resistor, inductor, capacitor networks in the element library.
- Individual resistor, inductor, and capacitor. These are multi-level models. Level-1 is basic component. Level-2 includes parasitic and leakage elements as lumped components in equivalent circuits.
- Combined R-L-C series branch
- Symmetrical three-phase branches of resistor, inductor, capacitor, and their combinations

User can define initial conditions of inductor currents and capacitor voltages for individual component. But the initial inductor currents and capacitor voltages for three-phase branches are all set at zero.

4.1.1 Individual Resistor

Image:

![Image of a resistor](image)

Attributes of Level-1 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Resistance, in Ohm</td>
</tr>
<tr>
<td>Voltage Rating</td>
<td>Voltage rating of the component, in V, for Level 2 model only.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display. If this flag is set 1, the current flowing through this component will be saved to display in SIMVIEW and Runtime Graphs. The current is positive when it flows into the dotted terminal of the branch.</td>
</tr>
</tbody>
</table>

Attributes of Level-2 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Resistance, in Ohm</td>
</tr>
<tr>
<td>Voltage Rating</td>
<td>Voltage rating of the component, in V.</td>
</tr>
<tr>
<td>Power Rating</td>
<td>Power rating of the component, in W.</td>
</tr>
<tr>
<td>Inductance ESL</td>
<td>Equivalent series inductance (ESL), in H.</td>
</tr>
<tr>
<td>Parallel Capacitance</td>
<td>Equivalent parallel parasitic capacitance, in F.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display. If this flag is set 1, the current flowing through this component will be saved to display in SIMVIEW and Runtime Graphs. The current is positive when it flows into the dotted terminal of the branch.</td>
</tr>
</tbody>
</table>
4.1.2 Individual Inductor

Attributes of Level-1 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inductance</td>
<td>Inductance, in H.</td>
</tr>
<tr>
<td>Initial Current</td>
<td>Initial inductor current, in A</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display</td>
</tr>
</tbody>
</table>

Attributes of Level-2 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inductance</td>
<td>Inductance, in H.</td>
</tr>
<tr>
<td>Peak Current Rating</td>
<td>Peak current rating of the inductor, in A.</td>
</tr>
<tr>
<td>Series Resistance</td>
<td>Equivalent series resistance (ESR), in Ohm.</td>
</tr>
<tr>
<td>Parallel Resistance</td>
<td>Leakage resistance in parallel with the inductor, in Ohm.</td>
</tr>
<tr>
<td>Parallel Capacitance</td>
<td>Parallel parasitic capacitance, in F.</td>
</tr>
<tr>
<td>Initial Current</td>
<td>Initial inductor current, in A</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display.</td>
</tr>
</tbody>
</table>

4.1.3 Individual and Electrolytic Capacitors

Images:
### Attributes of Level-1 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Capacitance</td>
<td>Capacitance, in F.</td>
</tr>
<tr>
<td>Initial Voltage</td>
<td>Initial capacitor voltage, in V</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current display</td>
</tr>
</tbody>
</table>

### Attributes of Level-2 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Capacitance</td>
<td>Capacitance, in F.</td>
</tr>
<tr>
<td>Voltage Rating</td>
<td>Voltage rating of the component, in V</td>
</tr>
<tr>
<td>RMS Current Rating</td>
<td>RMS current rating, in A.</td>
</tr>
<tr>
<td>Resistance ESR</td>
<td>Equivalent series resistance (ESR), in Ohm.</td>
</tr>
<tr>
<td>Inductance ESL</td>
<td>Equivalent series inductance (ESL), in H.</td>
</tr>
<tr>
<td>Leakage Resistance</td>
<td>Leakage resistance, in Ohm.</td>
</tr>
<tr>
<td>Initial Voltage</td>
<td>Initial capacitor voltage, in V</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display</td>
</tr>
</tbody>
</table>

### Equivalent Circuit:

![Equivalent Circuit Diagram]

### 4.1.4 Combined R-L-C Branch

#### Image:

![Image of Combined R-L-C Branch]

### Attributes for R-L-C Branch:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Resistance, in Ohm</td>
</tr>
<tr>
<td>Inductance</td>
<td>Inductance, in H</td>
</tr>
<tr>
<td>Capacitance</td>
<td>Capacitance, in F</td>
</tr>
<tr>
<td>Initial Current</td>
<td>Initial inductor current, in A</td>
</tr>
<tr>
<td>Initial Cap. Voltage</td>
<td>Initial capacitor voltage, in V</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for branch current waveform display</td>
</tr>
</tbody>
</table>

**Note:** For combined R-L-C brand, at least one of the parameters R, L, or C has to be a non-zero value.
4.1.5 Three-Phase R, L, C, and Combination Branches

Images:

Attributes for Three-Phase R, L, C, and Combination Branches:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Resistance, in Ohm</td>
</tr>
<tr>
<td>Inductance</td>
<td>Inductance, in H</td>
</tr>
<tr>
<td>Capacitance</td>
<td>Capacitance, in F</td>
</tr>
<tr>
<td>Current Flag A; Current Flag B; Current Flag C</td>
<td>Current flags for Phase A, B, and C of three-phase branches, respectively. If this flag is set 1, the current flowing through this branch will be saved to the file for display in SIMVIEW. It will also be available for display in the runtime graphs (under Simulate &gt;&gt; Runtime Graphs). The dot in the image indicates phase A. The current is positive when it flows into the dotted terminal of the branch.</td>
</tr>
</tbody>
</table>

4.1.6 3-Phase AC Cable

The 3-phase ac cable model takes into account inductive coupling and capacitances between phases.

Image:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Cable Length</td>
<td>Length of the cable, in m</td>
</tr>
<tr>
<td>Operating Frequency</td>
<td>Operating frequency of the cable, in Hz</td>
</tr>
<tr>
<td>Resistance R_d</td>
<td>Positive sequence resistance R_d of the cable, in Ohm</td>
</tr>
<tr>
<td>Reactance X_d</td>
<td>Positive sequence reactance X_d of the cable, in Ohm</td>
</tr>
<tr>
<td>Resistance R_o</td>
<td>Zero sequence resistance R_o of the cable, in Ohm</td>
</tr>
<tr>
<td>Reactance X_o</td>
<td>Zero sequence reactance X_o of the cable, in Ohm</td>
</tr>
<tr>
<td>Capacitance C_o</td>
<td>Zero sequence capacitance C_o of the cable, in F</td>
</tr>
</tbody>
</table>

In the image, the bottom node N or n on each side of the cable is the cable screen. It is generally connected to the ground on the side of the cable.

The cable parameters should be available from manufacturers’ datasheet. When they are not available, assuming that each phase of the cable has a resistance of $R$, self inductance of $L$, and mutual inductance of $M$, the positive sequence and zero sequence parameters can be calculated as follows:
\[ R_d = R \]
\[ X_d = \omega \cdot (L - M) \]
\[ R_o = R \]
\[ X_o = \omega \cdot (L + 2M) \]

where \( \omega = 2\pi f \) and \( f \) is the operating frequency in Hz.

### 4.1.7 Rheostat

A rheostat is a resistor with a tap.

**Image:**

![Rheostat Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Total Resistance</td>
<td>Total resistance of the rheostat ( R ) (between Node ( k ) and ( m )), in Ohm</td>
</tr>
<tr>
<td>Tap Position (0 to 1)</td>
<td>The tap position ( Tap ). The resistance between Node ( k ) and ( t ) is: ( R \times Tap ).</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for the current that flows into Node ( k ).</td>
</tr>
</tbody>
</table>

### 4.1.8 Saturable Inductor

A saturable inductor takes into account the saturation effect of the magnetic core.

**Image:**

![Saturable Inductor Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Current vs. Inductance</td>
<td>Characteristics of the current versus the inductance ( (i_1, L_1) ), ( (i_2, L_2) ), etc.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for the current display</td>
</tr>
</tbody>
</table>

The nonlinear \( B-H \) curve is represented by piecewise linear approximation. Since the flux density \( B \) is proportional to the flux linkage \( \lambda \) and the magnetizing force \( H \) is proportional to the current \( i \), the \( B-H \) curve can be represented by the \( \lambda-i \) curve instead, as shown below.

![B-H Curve Diagram](image)

The inductance is defined as: \( L = \frac{\lambda}{i} \), the ratio of \( \lambda \) vs. \( i \) at each point. The saturation characteristics are defined by a series of data points as: \( (i_1, L_1) \), \( (i_2, L_2) \), \( (i_3, L_3) \), etc.
Note that the defined saturation characteristics must be such that the flux linkage $\lambda$ is monotonically increasing. That is, $L_1*i_1 < L_2*i_2 < L_3*i_3$, etc.

Also, similar to the saturation characteristics in the real world, the slope of each linear segment must be monotonically decreasing as the current increases.

In certain situations, circuits that contain saturable inductors may fail to converge. Connecting a very small capacitor across the saturable inductor may help the convergence.

**4.1.9 Coupled Inductors**

Coupled inductors with two, three, four, five, and six branches are provided.

**Images:**

<table>
<thead>
<tr>
<th>2-branch</th>
<th>3-branch</th>
<th>4-branch</th>
<th>5-branch</th>
<th>6-branch</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Image" /></td>
<td><img src="image2.png" alt="Image" /></td>
<td><img src="image3.png" alt="Image" /></td>
<td><img src="image4.png" alt="Image" /></td>
<td><img src="image5.png" alt="Image" /></td>
</tr>
</tbody>
</table>

In the images, the small circle indicates the input terminal of inductor 1 while the small square, triangle, + sign, x sign, and * sign indicate the input terminal of inductor 2, 3, 4, 5, and 6.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$L_{ii}$ (self)</td>
<td>Self inductance of the inductor $i$, in H</td>
</tr>
<tr>
<td>$L_{ij}$ (mutual)</td>
<td>Mutual inductance between Inductor $i$ and $j$, in H</td>
</tr>
<tr>
<td>Initial Current $i_j$</td>
<td>Initial current in Inductor $i$</td>
</tr>
<tr>
<td>Current Flag $i_j$</td>
<td>Flag for the current printout in Inductor $i$</td>
</tr>
</tbody>
</table>

The following shows a coupled inductor with two branches.

```
\[
\begin{align*}
\frac{dv_1}{dt} &= L_{11}i_1 + L_{12}i_2 \\
\frac{dv_2}{dt} &= L_{21}i_1 + L_{22}i_2
\end{align*}
\]
```

Let $L_{11}$ and $L_{22}$ be the self-inductances of Branch 1 and 2, and $L_{12}$ and $L_{21}$ the mutual inductances, the branch voltages and currents have the following relationship:

\[
\begin{bmatrix}
  v_1 \\
  v_2
\end{bmatrix} = \begin{bmatrix}
  L_{11} & L_{12} \\
  L_{21} & L_{22}
\end{bmatrix} \begin{bmatrix}
  i_1 \\
  i_2
\end{bmatrix} + \begin{bmatrix}
  \frac{dv_1}{dt} \\
  \frac{dv_2}{dt}
\end{bmatrix}
\]

The mutual inductances between two windings are assumed to be always equal, i.e., $L_{12} = L_{21}$.

In the SPICE software, coupled inductors are defined by the self inductances and the coupling factors. For the coupled inductor with two branches, the coupling factor $K$ is defined as:
The mutual inductance is then calculated as:

\[ K = \frac{L_{12}}{\sqrt{L_{11} \cdot L_{22}}} \]

The coupling factor has a value between 0 and 1. When the coupling factor is 1, it is perfect coupling. Note that in PSIM, perfect coupling is not allowed. That is, the coupling factor cannot be equal to 1.

Also, when the leakage inductances are ignored (i.e. the coupling factor is close to 1), the self inductances are proportional to the turns ratio squared. That is, if Branch 1 has \( N_1 \) turns, and Branch 2 has \( N_2 \) turns:

\[ \frac{L_1}{L_2} = \frac{N_1^2}{N_2^2} \]

Example:

Two mutually coupled inductors have the self inductances and mutual inductance as: \( L_{11} = 1 \text{ mH}, \ L_{22} = 1.1 \text{ mH}, \) and \( L_{12} = L_{21} = 0.9 \text{ mH} \). The coupling factor is: \( K = 0.86 \). The specification of this element will be:

| \( L_{11} \) (self) | 1m |
| \( L_{12} \) (mutual) | 0.9m |
| \( L_{22} \) (self) | 1.1m |

4.1.10 Nonlinear Elements

The following elements with nonlinear voltage-current relationship are provided:

- Resistance-type \([v = f(i)]\)
- Resistance-type with additional input \([v = f(i,x)]\)
- Conductance-type \([i = f(v)]\)
- Conductance-type with additional input \([i = f(v,x)]\)

The additional input \( x \) must be a voltage signal.

Images:

<table>
<thead>
<tr>
<th>Nonlinear element</th>
<th>Nonlinear element (with additional input)</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Nonlinear element" /></td>
<td><img src="image2.png" alt="Nonlinear element with additional input" /></td>
</tr>
</tbody>
</table>

Attributes:

For resistance-type elements:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expression ( f(i) ) or ( f(i,x) )</td>
<td>Expression of ( v ) in terms of ( i ) and ( x ) ([v = f(i) \text{ or } v = f(i,x)])</td>
</tr>
<tr>
<td>Expression ( df/di )</td>
<td>The derivative of the voltage ( v ) versus current ( i ), i.e. ( df(i)/di )</td>
</tr>
<tr>
<td>Initial Value ( i_0 )</td>
<td>The initial value of the current ( i )</td>
</tr>
<tr>
<td>Lower Limit of ( i )</td>
<td>The lower limit of the current ( i )</td>
</tr>
<tr>
<td>Upper Limit of ( i )</td>
<td>The upper limit of the current ( i )</td>
</tr>
</tbody>
</table>
For conductance-type elements:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expression ( f(v) ) or ( f(v,x) )</td>
<td>Expression of ( i ) in terms of ( v ) and ( x ) [ [ i = f(v) \text{ or } i = f(v,x) ]]</td>
</tr>
<tr>
<td>Expression ( df/dv )</td>
<td>Derivative of the current ( i ) versus voltage ( v ), i.e. ( df/dv )</td>
</tr>
<tr>
<td>Initial Value ( v_o )</td>
<td>The initial value of the voltage ( v )</td>
</tr>
<tr>
<td>Lower Limit of ( v )</td>
<td>The lower limit of the voltage ( v )</td>
</tr>
<tr>
<td>Upper Limit of ( v )</td>
<td>The upper limit of the voltage ( v )</td>
</tr>
</tbody>
</table>

A good initial value and lower/upper limits will help the convergence of the solution.

**Example: Nonlinear Diode**

![Diode Circuit Diagram]

The nonlinear element (NONI) in the circuit above models a nonlinear diode. The diode current is expressed as a function of the voltage as: \( i = 10^{-14} \times (e^{40 \times v} - 1) \). In PSIM, the specifications of the nonlinear element will be:

<table>
<thead>
<tr>
<th>Expression ( f(v) )</th>
<th>1e-14*(EXP(40*v)-1)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expression ( df/dv )</td>
<td>40e-14<em>EXP(40</em>v)</td>
</tr>
<tr>
<td>Initial Value ( v_o )</td>
<td>0</td>
</tr>
<tr>
<td>Lower Limit of ( v )</td>
<td>-1e3</td>
</tr>
<tr>
<td>Upper Limit of ( v )</td>
<td>1</td>
</tr>
</tbody>
</table>

### 4.2 Switching Devices

There are two basic types of switching devices in PSIM. One is the switchmode type. It operates either in the cut-off region (off state) or saturation region (on state). The other is the linear type. It can operates in either cut-off, linear, or saturation region.

Switches in switchmode include the following:
- Diode and DIAC
- Thyristor and TRIAC
- Self-commutated switches:
  - npn and pnp bipolar junction transistor (BJT)
  - Insulated-Gate Bipolar Transistor (IGBT)
  - n-channel and p-channel Metal-Oxide-Semiconductor Field-Effect Transistor (MOSFET)
  - MOSFET with fixed on-resistance \( R_{DS(on)} \)
  - MOSFET with on-resistance \( R_{DS(on)} \) as a function of junction temperature
  - Gate-Turn-Off switch (GTO)
  - Bi-directional switch

Switchmode switch models are ideal. Both turn-on and turn-off transients are neglected.

A switch has an on-resistance of 10μΩ. When there is no R-L-C branch connected in parallel with the switch, a 10-MΩ resistor will be connected across the switch internally. This resistance can be viewed as the off-state resistance. In certain cases, this resistance may need to be modified. To change the off-state resistance to,
example, 100 MΩ connect a 100-MΩ in parallel to the switch. Since PSIM sees that there is already a resistor in parallel to the switch, the 10-MΩ resistor will not be added.

Snubber circuits are not required for switches.

Linear switches include the following:
- 3-State npn and pnp bipolar junction transistor
- 3-State n-channel and p-channel MOSFET

### 4.2.1 Diode

The conduction of a diode or LED is determined by circuit operating conditions. PSIM’s diode has 2 model levels:
- Level -1 Model: A diode is turned on when the positive bias voltage is greater than the threshold voltage, and is turned off when the current drops to zero.
- Level-2 Model: Includes leads parasitic inductance and reverse recovery parameters.

#### Attributes of the Level-1 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Forward Voltage</td>
<td>Forward voltage $V_{d,th}$ in V. A diode starts to conduct when the positive bias voltage is greater than $V_{d, th}$.</td>
</tr>
<tr>
<td>Resistance</td>
<td>On-resistance $R_d$, in Ohm, after it starts to conduct.</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Flag for the initial diode position. If it is 0, the diode is off. If it is 1, the diode is on.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Current flag for diode current display.</td>
</tr>
</tbody>
</table>

#### Attributes of the Level-2 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Forward Voltage</td>
<td>Forward voltage $V_{d, th}$ in V. A diode starts to conduct when the positive bias voltage is greater than $V_{d, th}$.</td>
</tr>
<tr>
<td>Resistance</td>
<td>On-resistance $R_d$, in Ohm, after it starts to conduct.</td>
</tr>
<tr>
<td>Parasitic Inductance</td>
<td>Series parasitic inductance, in H</td>
</tr>
<tr>
<td>Parallel Capacitance</td>
<td>Parallel capacitance between the diode anode and cathode, in F. If the capacitance value is 0, the capacitor is ignored and is removed from simulation.</td>
</tr>
<tr>
<td>Forward Current</td>
<td>Forward current $I_{fwd}$ under test conditions of diode reverse recovery characteristic, in A.</td>
</tr>
<tr>
<td>Peak Reverse Current</td>
<td>Peak reverse current $I_{rm}$ under test conditions, in A</td>
</tr>
<tr>
<td>Current Slope</td>
<td>Current slope $dl/dt$ under test conditions, in A/sec.</td>
</tr>
<tr>
<td>Reverse Recovery Time</td>
<td>Reverse recovery time $t_{rr}$ under test conditions, in sec.</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Flag for the initial diode position. If it is 0, the diode is off. If it is 1, the diode is on.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Current flag for diode current waveform display.</td>
</tr>
</tbody>
</table>
Diode v-i Characteristic:

![Diode v-i Characteristic Diagram]

Diode Level-2 Model Reverse Recovery Parameter Definitions:

![Diode Level-2 Model Reverse Recovery Parameter Definitions Diagram]

The reverse recovery time \( t_{rr} \) consists of two parts: \( t_a \) and \( t_b \). During the period \( t_a \), the current increases from 0 to \(-I_{rm}\). Based on JEDEC (Joint Electron Device Engineering Council), \( t_b \) is defined as the interval from the time of \(-I_{rm}\) to the time when the straight line from \(-I_{rm}\) through \(-0.25*I_{rm}\) (in red in the diagram) intersects with the time axis.

For further information on how to use the Level-2 model, please refer to the tutorial "Tutorial - Diode model with reverse recovery.pdf".

4.2.2 LED

A light-emitting diode (LED) emits light when it conducts. Its v-i characteristic is the same model as diode’s Level-1 model.

Image:

![LED Image]

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Forward Voltage</td>
<td>LED forward threshold voltage ( V_{d, th} ), in V. The LED starts to conduct and emit light when the positive bias voltage is greater than ( V_{d, th} ).</td>
</tr>
<tr>
<td>Resistance</td>
<td>LED on-resistance ( R_d ), in Ohm, after it starts to conduct.</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Flag for the initial LED position. If the flag is 0, the LED is off. If it is 1, the LED is on.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Current flag for LED current display.</td>
</tr>
</tbody>
</table>
4.2.3 Zener Diode and DIAC

Zener:

A zener diode is modeled by a circuit as shown below.

Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Breakdown Voltage</td>
<td>Breakdown voltage $V_B$ of the zener diode, in V</td>
</tr>
<tr>
<td>Forward Threshold</td>
<td>Threshold voltage of the forward conduction (from anode to cathode), in V</td>
</tr>
<tr>
<td>Voltage</td>
<td></td>
</tr>
<tr>
<td>Forward Resistance</td>
<td>On resistance of the forward conduction, in Ohm</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for zener current output (from anode to cathode)</td>
</tr>
</tbody>
</table>

When the zener diode is positively biased, it behaviors as a regular diode. When it is reverse biased, it will block the conduction as long as the cathode-anode voltage $V_{KA}$ is less than the breakdown voltage $V_B$. When $V_{KA}$ exceeds $V_B$, the voltage $V_{KA}$ will be clamped to $V_B$.

Note that when the zener is clamped, since the diode is modelled with an on-resistance of $10\mu\Omega$, the cathode-anode voltage will in fact be equal to: $V_{KA} = V_B + 10\mu\Omega \times I_{KA}$. Therefore, depending on the value of $I_{KA}$, $V_{KA}$ will be slightly higher than $V_B$. If $I_{KA}$ is very large, $V_{KA}$ can be substantially higher than $V_B$.

DIAC:

A DIAC is a bi-directional diode. A DIAC does not conduct until the breakover voltage is reached. After that, the DIAC goes into avalanche conduction, and the conduction voltage drop is the breakback voltage.

Image:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Breakover Voltage</td>
<td>Voltage at which breakover occurs and the DIAC begins to conduct, in V</td>
</tr>
<tr>
<td>Breakback Voltage</td>
<td>Conduction voltage drop, in V</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Current flag</td>
</tr>
</tbody>
</table>
4.2.4 Thyristor and TRIAC

A thyristor is controlled at turn-on. The turn-off is determined by circuit conditions.

A TRIAC is a device that can conduct current in both directions. It behaves in the same way as two opposite thyristors connected in parallel.

Images:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage Drop</td>
<td>Thyristor conduction voltage drop, in V</td>
</tr>
<tr>
<td>Holding Current</td>
<td>Minimum conduction current below which the device stops conducting and returns to the OFF state (for thyristor only)</td>
</tr>
<tr>
<td>Latching Current</td>
<td>Minimum ON state current required to keep the device in the ON state after the triggering pulse is removed (for thyristor only)</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Flag for the initial switch position (for thyristor only)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Flag for switch current output</td>
</tr>
</tbody>
</table>

Note that for the TRIAC device, the holding current and latching current are set to zero.

There are two ways to control a thyristor or TRIAC. One is to use a gating block, and the other is to use a switch controller. The gate node of a thyristor or TRIAC must be connected to either a gating block or a switch controller.

The following examples illustrate the control of a thyristor switch.

**Examples: Control of a Thyristor Switch**

This circuit on the left uses a switching gating block. The switching gating pattern and the frequency are pre-defined, and remain unchanged throughout the simulation. The circuit on the right uses an alpha switch controller. The delay angle alpha, in deg., is specified through the dc source in the circuit.
4.2.5 Transistor

The bipolar junction transistor (BJT) models in PSIM are ideal switching devices. Their behavior is a little bit different from that of the devices in real life. A BJT switch in PSIM will block reverse voltage (in this sense, it behaves like a GTO). Also, it is controlled by a voltage signal at the gate node, not a current.

An npn transistor is turned on when the gating signal is a logic high (when a voltage of 1V or higher is applied to the gate node) and the switch is positively biased (collector-emitter voltage is positive). A pnp transistor is turned on when the gating signal is a logic low and the switch is negatively biased (collector-emitter voltage is negative).

Images:

<table>
<thead>
<tr>
<th>nnp Transistor</th>
<th>pnp Transistor</th>
</tr>
</thead>
</table>

Attributes for npn Transistor and pnp Transistor:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Saturation Voltage</td>
<td>The saturation voltage $V_{ce_sat}$ for npn, or $V_{ec_sat}$ for pnp, in V</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag (0: off; 1: on)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag (0: no display; 1: display)</td>
</tr>
</tbody>
</table>

Example: Control of a npn Bipolar Junction Transistor

The circuit on the left uses a gating block, and the one on the right uses an on-off switch controller.

If the switch is controlled by a control circuit signal, as shown in the circuit on the right side, an on-off switch controller must be used at the gate node.

The following shows another example of controlling the BJT switch. The circuit on the left shows how a BJT switch is controlled in the real life. In this case, the gating voltage $V_B$ is applied to the transistor base drive circuit through a transformer, and the base current determines the conduction state of the transistor.

This circuit can be modelled and implemented in PSIM as shown on the right. A diode, $D_{be}$, with a conduction voltage drop of 0.7V, is used to model the pn junction between the base and the emitter. When the base current exceeds 0 (or a certain threshold value, in which case the base current will be compared to a dc source), the comparator output will be 1, applying the turn-on pulse to the transistor through the on-off switch controller.
4.2.6 MOSFET

The MOSFET switches consist of an active switch with an anti-parallel diode. The MOSFET is turned on when the gating signal is a logic high (when a voltage of 1V or higher is applied to the gate node) and the switch is positively biased (drain-source voltage is positive). It is turned off whenever the gating signal is low or the current drops to zero.

The p-channel MOSFET is turned on when the gating signal is a logic low and it is negatively biased (drain-source voltage is negative).

The switches MOSFET \( R_{DS(on)} \) and p-MOSFET \( R_{DS(on)} \) have on-resistance as a function of the junction temperature. In the images of MOSFET \( R_{DS(on)} \) and p-MOSFET \( R_{DS(on)} \), the node on top of the gate node is for defining the junction temperature. A voltage signal at this node will define the junction temperature \( T_j \) in \(^\circ\)C. For example, a voltage value of 25V would mean a junction temperature of 25\(^\circ\)C. The on-resistance of the MOSFET is a function of the junction temperature, as expressed below:

\[
R_{DS(on)} = R_{DS(on),b} \cdot (1 + K_T \cdot (T_j - T_{j,b}))
\]

A switch can be controlled by either a gating block or a switch controller. They must be connected to the gate (base) node of the switch.

Images:

<table>
<thead>
<tr>
<th>MOSFET</th>
<th>p-MOSFET</th>
</tr>
</thead>
<tbody>
<tr>
<td>![MOSFET Image]</td>
<td>![p-MOSFET Image]</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>On Resistance</td>
<td>The on resistance ( R_{ds_on} ) of the MOSFET, in Ohm</td>
</tr>
<tr>
<td>Diode Forward Voltage</td>
<td>Anti-parallel diode forward threshold voltage, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>Anti-parallel diode on resistance, in Ohm</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag for the transistor only (0: off; 1: on)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag for the whole module (the transistor plus the diode) (0: no display; 1: display)</td>
</tr>
</tbody>
</table>
**Attributes** for MOSFET (RDS(on)) and p-MOSFET (RDS(on)):

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Tj at Test</td>
<td>Junction temperature $T_j$ at test, in °C</td>
</tr>
<tr>
<td>RDS(on) at Test</td>
<td>On-resistance $R_{DS(on)}$ at test, in Ohm</td>
</tr>
<tr>
<td>Temperature Coefficient</td>
<td>Temperature coefficient $K_T$ of the on-resistance, in $1/°C$</td>
</tr>
<tr>
<td>Diode Forward Voltage</td>
<td>Anti-parallel diode forward threshold voltage, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>Anti-parallel diode on resistance, in Ohm</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag for the transistor only (0: off; 1: on)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag for the whole module (the transistor plus the diode)</td>
</tr>
</tbody>
</table>

The following examples illustrate the control of a MOSFET switch.

![MOSFET Switch Diagrams](image)

The circuit on the left uses a gating block, and the one on the right uses an on-off switch controller. The gating signal is determined by the comparator output.

### 4.2.7 IGBT

An IGBT switch consists of an active switch with an anti-parallel diode. It is turned on when the gating signal is high (when a voltage of 1V or higher is applied to the gate node) and the switch is positively biased (collector-emitter voltage is positive). It is turned off whenever the gating signal is low or the current drops to zero.

**Image:**

![IGBT Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Saturation Voltage</td>
<td>Saturation voltage $V_{ce_sat}$ of the IGBT, in V</td>
</tr>
<tr>
<td>Transistor Resistance</td>
<td>Transistor on resistance, in Ohm</td>
</tr>
<tr>
<td>Diode Forward Voltage</td>
<td>Anti-parallel diode forward threshold voltage, in V</td>
</tr>
</tbody>
</table>
4.2.8 IGBT-RB

An IGBT-RB switch consists of an active switch with reverse blocking capability and without an anti-parallel diode. It is turned on when the gating signal is high (when a voltage of 1V or higher is applied to the gate node) and the switch is positively biased (collector-emitter voltage is positive). It is turned off whenever the gating signal is low or the current drops to zero.

Two versions of IGBT-RB are provided: a single switch, and a dual package with two back-to-back switches.

**Images:**

![IGBT-RB Image]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Saturation Voltage</td>
<td>Saturation voltage Vce_sat of the IGBT, in V</td>
</tr>
<tr>
<td>Transistor Resistance</td>
<td>Transistor on resistance, in Ohm</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag for the switch, or in the case of the dual package, for Switch 1 or 2 (0: off; 1: on)</td>
</tr>
<tr>
<td>or Initial Position 1 or 2</td>
<td></td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag for the whole module (the transistor plus the diode)</td>
</tr>
</tbody>
</table>

For the dual package, when the element is placed in the upright position, Switch 1 is on the left and Switch 2 is on the right.

4.2.9 GTO

A GTO switch is a symmetrical device with both forward-blocking and reverse-blocking capabilities.

**Images:**

![GTO Image]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage Drop</td>
<td>GTO conduction voltage drop, in V</td>
</tr>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag (0: off; 1: on)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag (0: no display; 1: display)</td>
</tr>
</tbody>
</table>
4.2.10 Bi-Directional Switches

A bi-directional switch conducts current in both directions.

Three types of bi-directional switches are provided: single-phase switch, three-phase switch, and push button switch.

**Images:**

<table>
<thead>
<tr>
<th>Single switch</th>
<th>3-phase switch</th>
<th>Push button switch</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Single switch diagram" /></td>
<td><img src="image2.png" alt="3-phase switch diagram" /></td>
<td><img src="image3.png" alt="Push button switch diagram" /></td>
</tr>
</tbody>
</table>

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Position</td>
<td>Initial switch position flag (for single switch only).</td>
</tr>
<tr>
<td>Initial Position (for Phase A/B/C)</td>
<td>Initial switch position for Phase A, or B, or C.</td>
</tr>
<tr>
<td>Switch Position</td>
<td>Switch position can be either &quot;On&quot; or &quot;Off&quot; (for push button switch only).</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Switch current flag (for single switch only).</td>
</tr>
<tr>
<td>Current Flag (for Phase A/B/C)</td>
<td>Switch current flag for Phase A, or B, or C.</td>
</tr>
</tbody>
</table>

In the 3-phase switch image, the phase with a dot is Phase A.

For single and 3-phase bi-directional switches, they are on when the gating signal is high, and are off when the gating signal is low, regardless of the voltage bias conditions. For the push button switch, the switch position is set directly from the parameter input.

4.2.11 Linear Switches

Linear switches, which can operate in three states, include npn and pnp BJT, and n-channel and p-channel MOSFET. BJT devices can operate in either cut-off, linear, or saturation state. MOSFET devices can operate in either cut-off, active, or ohmic state.

MOSFET (3-state) has 2 level models. Level-1 is the basic MOSFET 3-state model while Level-2 takes the intrinsic and parasitic components into consideration.

**Images:**

<table>
<thead>
<tr>
<th>npn Transistor (3-state)</th>
<th>pnp Transistor (3-state)</th>
<th>MOSFET (3-state)</th>
<th>p-MOSFET (3-state)</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image4.png" alt="npn Transistor" /></td>
<td><img src="image5.png" alt="pnp Transistor" /></td>
<td><img src="image6.png" alt="MOSFET" /></td>
<td><img src="image7.png" alt="p-MOSFET" /></td>
</tr>
</tbody>
</table>
Attributes for npn Transistor (3-state) and pnp Transistor (3-state):

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Current Gain beta</td>
<td>Transistor current gain $\beta$, defined as: $\beta = \frac{I_c}{I_b}$</td>
</tr>
<tr>
<td>Bias Voltage $V_r$</td>
<td>Forward bias voltage, in V, between base and emitter for the npn transistor, or between emitter and base for the pnp transistor.</td>
</tr>
<tr>
<td>$V_{ce,sat}$ (or $V_{ec,sat}$ for pnp)</td>
<td>Saturation voltage, in V, between collector and emitter for the npn transistor, and between emitter and collector for the pnp transistor.</td>
</tr>
</tbody>
</table>

Attributes for MOSFET (3-state) and p-MOSFET (3-state) Level-1 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>On Resistance</td>
<td>On resistance $R_{DS(on)}$ of the MOSFET, in Ohm</td>
</tr>
<tr>
<td>Threshold Voltage $V_{gs(th)}$</td>
<td>Threshold voltage of the gate-to-source voltage, in V, beyond which the MOSFET starts to conduct.</td>
</tr>
<tr>
<td>Transconductance $g_m$</td>
<td>Transconductance $g_m$ of the MOSFET.</td>
</tr>
<tr>
<td>Diode Forward Voltage</td>
<td>Forward voltage of the anti-parallel diode, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the anti-parallel diode, in Ohm</td>
</tr>
</tbody>
</table>

Attributes for MOSFET (3-state) and p-MOSFET (3-state) Level-2 Model:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$V_{breakdown}$ (drain-source)</td>
<td>Maximum drain-source voltage without causing avalanche breakdown, in V.</td>
</tr>
<tr>
<td>On Resistance</td>
<td>On resistance $R_{DS(on)}$ of the MOSFET, in Ohm</td>
</tr>
<tr>
<td>Gate Threshold Voltage $V_{gs(th)}$</td>
<td>Threshold voltage of the gate-to-source voltage, in V, above which, the MOSFET starts to conduct.</td>
</tr>
<tr>
<td>Internal Gate Resistance</td>
<td>Internal gate resistance, in Ohm.</td>
</tr>
<tr>
<td>Transconductance $g_m$</td>
<td>Transconductance $g_m$ of the MOSFET.</td>
</tr>
<tr>
<td>Capacitance $C_{gs}$</td>
<td>Gate-to-source intrinsic capacitance, in F.</td>
</tr>
<tr>
<td>Capacitance $C_{gd}$</td>
<td>Gate-to-drain intrinsic capacitance, in F.</td>
</tr>
<tr>
<td>Capacitance $C_{ds}$</td>
<td>Output capacitance between drain and source, in F.</td>
</tr>
<tr>
<td>Diode Forward Voltage</td>
<td>Forward voltage of the anti-parallel diode, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the anti-parallel diode, in Ohm</td>
</tr>
</tbody>
</table>

A linear transistor is controlled by the base current $I_b$. It can operate in one of the three regions: cut-off (off state), linear, and saturation region (on state).

The properties of a npn transistor in these regions are:
- Cut-off region: $V_{be} < V_r; \quad I_b = 0; \quad I_c = 0$
- Linear region: $V_{be} = V_r; \quad I_c = \beta I_b; \quad V_{ce} > V_{ce,sat}$
- Saturation region: $V_{be} = V_r; \quad I_c < \beta I_b; \quad V_{ce} = V_{ce,sat}$

where $V_{be}$ is the base-emitter voltage, $V_{ce}$ is the collector-emitter voltage, and $I_c$ is the collector current.

The properties of a pnp transistor in these regions are:
- Cut-off region: $V_{eb} < V_r; \quad I_b = 0; \quad I_c = 0$
- Linear region: $V_{eb} = V_r; \quad I_c = \beta I_b; \quad V_{ec} > V_{ec,sat}$
- Saturation region: \( V_{eb} = V_{r}; \quad I_c < \beta \# I_b; \quad V_{cc} = V_{cc,sat} \)

where \( V_{eb} \) is the emitter-base voltage, \( V_{cc} \) is the emitter-collector voltage, and \( I_c \) is the collector current.

A linear MOSFET device is controlled by the gate-to-source voltage \( V_{gs} \). It can operate in one of the three regions: cut-off (off state), active, and ohmic region (on state).

The properties of a n-channel MOSFET device in these regions are:
- Cut-off region: \( V_{gs} < V_{gs(th)}; \quad I_d = 0 \)
- Active region: \( V_{gs} > V_{gs(th)} \) and \( V_{gs} - V_{gs(th)} < V_{ds}; \quad I_d = g_m \# (V_{gs} - V_{gs(th)}) \)
- Ohmic region: \( V_{gs} > V_{gs(th)} \) and \( V_{gs} - V_{gs(th)} > V_{ds}; \quad I_d = V_{ds} / R_{DS(on)} \)

where \( V_{gs} \) is the gate-source voltage, \( V_{ds} \) is the drain-source voltage, and \( I_d \) is the drain current.

The properties of a p-channel MOSFET device in these regions are:
- Cut-off region: \( V_{gs} > V_{gs(th)}; \quad I_d = 0 \)
- Active region: \( V_{gs} < V_{gs(th)} \) and \( V_{gs} - V_{gs(th)} > V_{ds}; \quad I_d = g_m \# (V_{gs} - V_{gs(th)}) \)
- Ohmic region: \( V_{gs} < V_{gs(th)} \) and \( V_{gs} - V_{gs(th)} < V_{ds}; \quad I_d = V_{ds} / R_{DS(on)} \)

Note that for 3-state npn/pnp BJT and n-channel/p-channel MOSFET, the base node (gate node) is a power node, and must be connected to a power circuit component (such as a resistor or a source). It can not be connected to a gating block or a switch controller.

**Examples: Circuits Using the Linear Transistor Switch**

Examples below illustrate the use of linear switches. The circuit on the left is a linear voltage regulator circuit, and the transistor operates in the linear mode. The circuit on the right is a simple test circuit.

![Circuits Using the Linear Transistor Switch](image)

**4.2.12 Switch Gating Block**

A switch gating block defines the gating pattern of a switch or a switch module. The gating pattern can be specified either directly (the element is called *Gating Block* in the library) or in a text file (the element is called *Gating Block (file)* in the library).

Note that a switch gating block can be connected to the gate node of a switch ONLY. It can not be connected to any other elements.

**Image:**

![Switch Gating Block](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>Operating frequency of the switch or switch module connected to the gating block, in Hz</td>
</tr>
</tbody>
</table>
The number of switching points is defined as the total number of switching actions in one period. Each turn-on or turn-off action is counted as one switching point. For example, if a switch is turned on and off once in one cycle, the number of switching points will be 2.

For the *Gating Block* element, the file for the gating table must be in the same directory as the schematic file. The gating table file has the following format:

\[
\begin{align*}
n \\
G1 \\
G2 \\
\vdots \\
Gn
\end{align*}
\]

where G1, G2, ..., Gn are the switching points.

**Example:**

Assume that a switch operates at 2000 Hz and has the following gating pattern in one period:

![Gating Pattern Diagram](image)

The specification of the *Gating Block* element for this switch will be:

<table>
<thead>
<tr>
<th>Frequency</th>
<th>2000.</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of Points</td>
<td>6</td>
</tr>
<tr>
<td>Switching Points</td>
<td>35. 92. 175. 187. 345. 357.</td>
</tr>
</tbody>
</table>

The gating pattern has 6 switching points (3 pulses). The corresponding switching angles are 35°, 92°, 175°, 187°, 345°, and 357°, respectively.

If the *Gating Block (file)* element is used instead, the specification will be:

<table>
<thead>
<tr>
<th>Frequency</th>
<th>2000.</th>
</tr>
</thead>
<tbody>
<tr>
<td>File for Gating Table</td>
<td>test.tbl</td>
</tr>
</tbody>
</table>

The file “test.tbl” will contain the following:

<table>
<thead>
<tr>
<th>No. of Points</th>
<th>Number of switching points (for the <em>Gating Block</em> element only)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Switching Points</td>
<td>Switching points, in deg. If the frequency is zero, the switching points is in second. (for the <em>Gating Block</em> element only)</td>
</tr>
<tr>
<td>File for Gating Table</td>
<td>Name of the file that stores the gating table (for the <em>Gating Block (file)</em> element only)</td>
</tr>
</tbody>
</table>
4.2.13 Single-Phase Switch Modules

Built-in single-phase diode bridge module and thyristor bridge module are provided. The images and internal connections of the modules are shown below.

Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Diode Threshold Voltage or Voltage Drop</td>
<td>Threshold voltage of the diode, or forward voltage drop of the thyristor, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the diode, in Ohm (for diode bridges only)</td>
</tr>
<tr>
<td>Init. Position (_i)</td>
<td>Initial position for Switch (_i)</td>
</tr>
<tr>
<td>Current Flag (_i)</td>
<td>Current flag for Switch (_i)</td>
</tr>
</tbody>
</table>

Node \(C_t\) at the bottom of the thyristor module is the gating control node for Switch 1. For the thyristor module, only the gating signal for Switch 1 needs to be specified. The gating signals for other switches will be derived internally in the program.

Similar to the single thyristor switch, a thyristor bridge can also be controlled by either a gating block or an alpha controller, as shown in the following examples.

Examples: Control of a Thyristor Bridge

The gating signal for the circuit on the left is specified through a gating block, and the gating signal for the circuit on the right is provided through an alpha controller. A major advantage of the alpha controller is that the delay angle \(\alpha\) of the thyristor bridge, in deg., can be directly controlled.
4.2.14 Three-Phase Switch Modules

The following figure shows three-phase switch modules and the internal circuit connections. A three-phase voltage source inverter module VS13 consists of either MOSFET-type or IGBT-type switches. A current source inverter module CS13 consists of GTO-type switches, or equivalently IGBT in series with diodes.

Images:

Attributes for the diode bridge:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Diode Threshold Voltage</td>
<td>Threshold voltage drop of the diode, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the diode, in Ohm</td>
</tr>
<tr>
<td>Init. Position _i</td>
<td>Initial position for Switch _i</td>
</tr>
<tr>
<td>Current Flag _i</td>
<td>Current flag for Switch _i</td>
</tr>
</tbody>
</table>
Attributes for thyristor bridges:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage Drop</td>
<td>Conduction voltage drop of the thyristor, in V</td>
</tr>
<tr>
<td>Init. Position (_i)</td>
<td>Initial position for Switch (_i)</td>
</tr>
<tr>
<td>Current Flag (_i)</td>
<td>Current flag for Switch (_i)</td>
</tr>
</tbody>
</table>

Attributes for VSI3 bridge (with MOSFET switches):

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>On Resistance</td>
<td>On resistance of the MOSFET transistor, in Ohm</td>
</tr>
<tr>
<td>Diode Threshold Voltage</td>
<td>Threshold voltage drop of the diode, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the diode, in Ohm</td>
</tr>
<tr>
<td>Init. Position (_i)</td>
<td>Initial position for Switch (_i)</td>
</tr>
<tr>
<td>Current Flag (_i)</td>
<td>Current flag for Switch (_i)</td>
</tr>
</tbody>
</table>

Attributes for VSI3 bridge (with IGBT switches):

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Saturation Voltage</td>
<td>Saturation voltage (V_{ce_sat}) of the IGBT transistor, in Ohm</td>
</tr>
<tr>
<td>Transistor Resistance</td>
<td>On resistance of the IGBT transistor, in Ohm</td>
</tr>
<tr>
<td>Diode Threshold Voltage</td>
<td>Threshold voltage drop of the anti-parallel diode, in V</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>On resistance of the anti-parallel diode, in Ohm</td>
</tr>
<tr>
<td>Init. Position (_i)</td>
<td>Initial position for Switch (_i)</td>
</tr>
<tr>
<td>Current Flag (_i)</td>
<td>Current flag for Switch (_i)</td>
</tr>
</tbody>
</table>

Attributes for the CSI3 bridge:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage Drop</td>
<td>Forward conduction voltage drop of the switch, in V</td>
</tr>
<tr>
<td>Resistance</td>
<td>Forward on resistance of the switch, in Ohm</td>
</tr>
<tr>
<td>Init. Position (_i)</td>
<td>Initial position for Switch (_i)</td>
</tr>
<tr>
<td>Current Flag (_i)</td>
<td>Current flag for Switch (_i)</td>
</tr>
</tbody>
</table>

Similar to single-phase modules, only the gating signal for Switch 1 need to be specified for three-phase modules. Gating signals for other switches will be automatically derived. For the 3-phase half-wave thyristor bridge, the phase shift between two consecutive switches is 120°. For all other bridges, the phase shift is 60°.

Thyristor bridges can be controlled by an alpha controller. Similarly, voltage/current source inverters can be controlled by a PWM lookup table controller.

The following examples illustrate the control of three-phase thyristor and voltage source inverter modules.
Example: Control of Three-Phase Thyristor and VSI Modules

The thyristor circuit on the left uses an alpha controller. For a three-phase circuit, the zero-crossing of the voltage $V_{ac}$ corresponds to the moment when the delay angle alpha is equal to zero. This signal is used to provide synchronization to the controller.

The circuit on the right uses a PWM lookup table controller. The PWM patterns are stored in a lookup table in a text file. The gating pattern is selected based on the modulation index. Other inputs of the PWM lookup table controller include the delay angle, the synchronization, and the enable/disable signal. A detailed description of the PWM lookup table controller is given in the *Switch Controllers* section.

### 4.3 Transformers

#### 4.3.1 Ideal Transformer

An ideal transformer has no losses and no leakage flux.

**Images:**

<table>
<thead>
<tr>
<th>$N_p$</th>
<th>$N_s$</th>
<th>$N_p$</th>
<th>$N_s$</th>
</tr>
</thead>
</table>

The winding with the larger dot is the primary, and the other winding is the secondary.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$N_p$ (primary)</td>
<td>No. of turns of the primary winding</td>
</tr>
<tr>
<td>$N_s$ (secondary)</td>
<td>No. of turns of the secondary winding</td>
</tr>
</tbody>
</table>

Since the turns ratio is equal to the ratio of the rated voltages, the number of turns can be replaced by the rated voltage at each side.
### 4.3.2 Single-Phase Transformers

Single-phase transformers with 1 or 2 primary windings and 1 to 6 secondary windings are provided, as shown below.

**Images:**

![Diagram of single-phase transformers with various windings](image)

In the images, \( p \) refers to primary, \( s \) refers to secondary, and \( t \) refers to tertiary. The winding with the largest dot is the primary winding or first primary winding. For the multiple winding transformers, the sequence of the windings is from the top to the bottom. For the transformers with 2 or 3 windings, the attributes are as follows.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_p ) (primary); ( R_s ) (secondary); ( R_t ) (tertiary)</td>
<td>Resistance of the primary/secondary/tertiary winding, in Ohm</td>
</tr>
<tr>
<td>( L_p ) (pri. leakage); ( L_s ) (sec. leakage); ( L_t ) (ter. leakage)</td>
<td>Leakage inductance of the primary/secondary/tertiary winding, in H (seen from the primary)</td>
</tr>
<tr>
<td>( L_m ) (magnetizing)</td>
<td>Magnetizing inductance, in H</td>
</tr>
<tr>
<td>( N_p ) (primary); ( N_s ) (secondary); ( N_t ) (tertiary)</td>
<td>No. of turns of the primary/secondary/tertiary winding</td>
</tr>
</tbody>
</table>

All the resistances and inductances are referred to the primary winding side. If there are multiple primary windings, they are referred to the first primary winding side.

For a transformer with more than 1 primary winding or more than 3 secondary windings, the attributes are as follows.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_{p,i} ) (primary ( i )); ( R_{s,i} ) (secondary ( i ))</td>
<td>Resistance of the ( i )th primary/secondary/tertiary winding, in Ohm</td>
</tr>
</tbody>
</table>
All the resistances and inductances are referred to the first primary winding side.

**Modeling of a Transformer:**

A transformer is modeled as coupled inductors. For example, a single-phase two-winding transformer is modeled as two coupled inductors. The equivalent circuit can be shown as:

![Equivalent Circuit Diagram]

In the circuit, \( R_p \) and \( R_s \) are the primary and secondary winding resistances; \( L_p \) and \( L_s \) are the primary and secondary winding leakage inductances; and \( L_m \) is the magnetizing inductance. All the values are referred to the primary side.

**Example:**

A single-phase two-winding transformer has a winding resistance of 0.002 Ohm and leakage inductance of 1 mH at both the primary and the secondary side (all the values are referred to the primary). The magnetizing inductance is 100 mH, and the turns ratio is \( N_p : N_s = 220 : 440 \). The transformer will be specified as:

<table>
<thead>
<tr>
<th></th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_p ) (primary)</td>
<td>2m</td>
</tr>
<tr>
<td>( R_s ) (secondary)</td>
<td>2m</td>
</tr>
<tr>
<td>( L_p ) (primary)</td>
<td>1m</td>
</tr>
<tr>
<td>( L_s ) (secondary)</td>
<td>1m</td>
</tr>
<tr>
<td>( L_m ) (magnetizing)</td>
<td>100m</td>
</tr>
<tr>
<td>( N_p ) (primary)</td>
<td>220</td>
</tr>
<tr>
<td>( N_s ) (secondary)</td>
<td>440</td>
</tr>
</tbody>
</table>

### 4.3.3 Three-Phase Transformers

Two-winding and three-winding transformer modules are provided, as shown below. They all have 3-leg cores.

- 3-phase transformer (windings unconnected)
- 3-phase Y/Y and Y/Δ connected transformers
- 3-phase 3-winding transformer (windings unconnected)
- 3-phase 3-winding Y/Y/Δ and Y/Δ/Δ connected transformers
- 3-phase 3-winding Y/Z1, Y/Z2, Δ/Z1, and Δ/Z2 phase-shifting transformers
- 3-phase 4-winding transformer (windings unconnected)
- 3-phase 6-winding transformer (windings unconnected)
Attributes for all transformers except phase-shifting transformers:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>R_p (primary); R_s (secondary); R_t (tertiary)</td>
<td>Resistance of the primary/secondary/tertiary winding, in Ohm</td>
</tr>
<tr>
<td>L_p (pri. leakage); L_s (sec. leakage); L_t (ter. leakage)</td>
<td>Leakage inductance of the primary/secondary/tertiary winding, in H</td>
</tr>
<tr>
<td>L_m (magnetizing)</td>
<td>Magnetizing inductance, in H (seen from the primary side)</td>
</tr>
<tr>
<td>N_p (primary); N_s (secondary); N_t (tertiary)</td>
<td>No. of turns of the primary/secondary/tertiary winding</td>
</tr>
</tbody>
</table>
Attributes for phase-shifting transformers:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>(R_p) (primary); (R_{s1}) (secondary 1); (R_{s2}) (secondary 2)</td>
<td>Resistance of the primary/1\textsuperscript{st} secondary/2\textsuperscript{nd} secondary winding, in Ohm</td>
</tr>
<tr>
<td>(L_p) (primary leakage); (L_{s1}) (secondary 1 leakage); (L_{s2}) (secondary 2 leakage)</td>
<td>Leakage inductance of the primary/1\textsuperscript{st} secondary/2\textsuperscript{nd} secondary winding, in H</td>
</tr>
<tr>
<td>(L_m) (magnetizing)</td>
<td>Magnetizing inductance, in H (seen from the primary side)</td>
</tr>
<tr>
<td>(N_p) (primary); (N_{s1}) (secondary 1); (N_{s2}) (secondary 2)</td>
<td>Number of turns of the primary/1\textsuperscript{st} secondary/2\textsuperscript{nd} secondary winding</td>
</tr>
</tbody>
</table>

In the images, \(P\) refers to primary, \(S\) refers to secondary, and \(T\) refers to tertiary. All resistances and inductances are referred to the primary or the first primary winding side.

Three-phase transformers are modeled in the same way as single-phase transformers.

For the 3-phase phase-shifting transformers, let the angle \(\delta\) be the phase difference between the secondary line voltage \(V_{ab}\) and the primary line voltage \(V_{AB}\). The relationship between the angle and the winding turns are:

For the Y/Z1 transformer:

\[
\frac{N_{s2}}{N_{s1} + N_{s2}} = \frac{\sin(30^\circ - \delta)}{\sin(30^\circ + \delta)}, \quad 0^\circ \leq \delta \leq 30^\circ
\]

\[
\frac{N_p}{N_{s1} + N_{s2}} = \frac{1}{2 \sin(30^\circ + \delta)} \cdot \frac{V_{AB}}{V_{ab}}
\]

For the Y/Z2 transformer:

\[
\frac{N_{s2}}{N_{s1} + N_{s2}} = \frac{\sin(30^\circ - |\delta|)}{\sin(30^\circ + |\delta|)}, \quad -30^\circ \leq \delta \leq 0^\circ
\]

\[
\frac{N_p}{N_{s1} + N_{s2}} = \frac{1}{2 \sin(30^\circ + |\delta|)} \cdot \frac{V_{AB}}{V_{ab}}
\]

For the Delta/Z1 transformer:

\[
\frac{N_{s2}}{N_{s1} + N_{s2}} = \frac{\sin(|\delta|)}{\sin(60^\circ - |\delta|)}, \quad -30^\circ \leq \delta \leq 0^\circ
\]

\[
\frac{N_p}{N_{s1} + N_{s2}} = \frac{\sqrt{3}}{2 \sin(60^\circ - |\delta|)} \cdot \frac{V_{AB}}{V_{ab}}
\]

For the Delta/Z2 transformer:

\[
\frac{N_{s2}}{N_{s1} + N_{s2}} = \frac{\sin(60^\circ - |\delta|)}{\sin(|\delta|)}, \quad -60^\circ \leq \delta \leq -30^\circ
\]

\[
\frac{N_p}{N_{s1} + N_{s2}} = \frac{\sqrt{3}}{2 \sin(|\delta|)} \cdot \frac{V_{AB}}{V_{ab}}
\]
The table below shows typical transformer turns ratios and delay angles.

<table>
<thead>
<tr>
<th>d (deg)</th>
<th>$N_{S2}/(N_{S1}+N_{S2})$</th>
<th>$N_{P}/(N_{S1}+N_{S2})*V_{ab}/V_{AB}$</th>
</tr>
</thead>
<tbody>
<tr>
<td>30</td>
<td>0</td>
<td>0.577</td>
</tr>
<tr>
<td>20</td>
<td>0.227</td>
<td>0.653</td>
</tr>
<tr>
<td>15</td>
<td>0.366</td>
<td>0.707</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>-15</td>
<td>0.366</td>
<td>0.707</td>
</tr>
<tr>
<td>-20</td>
<td>0.227</td>
<td>0.653</td>
</tr>
<tr>
<td>-30</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>-40</td>
<td>0.532</td>
<td>0.777</td>
</tr>
<tr>
<td>-45</td>
<td>0.366</td>
<td>1.225</td>
</tr>
<tr>
<td>-60</td>
<td>0</td>
<td>1</td>
</tr>
</tbody>
</table>

**4.3.4 Three-Phase Transformer with Saturation**

A three-phase three-winding transformer that can take into account saturation and residual flux is provided.

**Image:**

![Diagram of three-phase transformer with saturation](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operating Voltage (phase)</td>
<td>Transformer primary side rms voltage per phase under the circuit operating condition, in V</td>
</tr>
<tr>
<td>Operating Frequency</td>
<td>Operating frequency of the transformer, in Hz</td>
</tr>
<tr>
<td>$R_p$ (primary)</td>
<td>Resistance of the primary winding, in Ohm</td>
</tr>
<tr>
<td>$L_p$ (pri. leakage)</td>
<td>Leakage inductance of the primary winding, in H</td>
</tr>
<tr>
<td>$R_s$ (secondary)</td>
<td>Resistance of the secondary winding, in Ohm (referred to the primary side)</td>
</tr>
<tr>
<td>$L_s$ (sec. leakage)</td>
<td>Leakage inductance of the secondary winding, in H (referred to the primary side)</td>
</tr>
<tr>
<td>$R_m$ (core losses)</td>
<td>Resistance that represents transformer core losses, in Ohm</td>
</tr>
<tr>
<td>$I_m$ vs. $L_m$</td>
<td>Values of the magnetizing current $I_m$ (in A) vs. the magnetizing inductance $L_m$ (in H) that defines the magnetizing characteristics seen from the primary winding</td>
</tr>
<tr>
<td>Phase A Residual Flux</td>
<td>Phase A residual flux, in per unit value</td>
</tr>
<tr>
<td>Phase B Residual Flux</td>
<td>Phase B residual flux, in per unit value</td>
</tr>
<tr>
<td>Phase C Residual Flux</td>
<td>Phase C residual flux, in per unit value</td>
</tr>
<tr>
<td>$N_p$ (primary)</td>
<td>Number of turns of the primary winding</td>
</tr>
<tr>
<td>$N_s$ (secondary)</td>
<td>Number of turns of the secondary winding</td>
</tr>
</tbody>
</table>
All the resistances and inductances are referred to the primary side. In the images, \( p \) refers to the primary side and \( s \) refers to the secondary side. The node \( en \) is a control node, to be connected to a control logic signal. The moment when the signal changes from 0 to 1 indicates the moment that the transformer is energized.

Note that the operating voltage refers to the voltage per phase in the actual operating condition, not necessarily the rated voltage. For example, if a transformer rated at 63kV (primary side line-to-line rms) operates under the rated condition, and if the primary winding is connected in \( Y \), the operating voltage per phase will be \( 63,000/\sqrt{3} \) V. If the primary winding is connected in \( \Delta \), the operating voltage per phase will be 63,000V. If the same transformer is connected in \( \Delta \) but the actual operating voltage is only 60,000V, for example, the operating voltage per phase will be 60,000V instead.

### 4.4 Magnetic Elements

A set of magnetic elements, including winding, leakage flux path, air gap, linear core, and saturable core, is provided to model magnetic devices. These elements are the basic building blocks of magnetic equivalent circuits, and they provide a very powerful and convenient way of modeling any types of magnetic devices.

Different unit systems have been used in the magnetic circuit analysis. The table below shows magnetic quantities in the SI (System International) and the mixed CGS (Centimeter Gram Second) unit systems, and their conversion.

<table>
<thead>
<tr>
<th>Quantity</th>
<th>SI Unit</th>
<th>CGS Unit</th>
<th>CGS-SI Conversion</th>
</tr>
</thead>
<tbody>
<tr>
<td>Flux ( \phi )</td>
<td>Weber</td>
<td>Maxwell</td>
<td>1 Weber = ( 10^8 ) Maxwell</td>
</tr>
<tr>
<td>Flux Density ( B )</td>
<td>Tesla</td>
<td>Gauss</td>
<td>1 Tesla = ( 10^4 ) Gauss</td>
</tr>
<tr>
<td>Field Intensity ( H )</td>
<td>A*Turns/m</td>
<td>Oersted</td>
<td>1 A*Turns/m = ( \frac{4\pi}{1000} ) Oersted</td>
</tr>
<tr>
<td>Magnetomotive Force (mmf) ( F )</td>
<td>A*Turns</td>
<td>Gilbert</td>
<td>1 A*Turns = ( \frac{4\pi}{10} ) Gilbert</td>
</tr>
<tr>
<td>Permeability ( \mu_0 ) (in space)</td>
<td>( 4\pi \times 10^{-7} )</td>
<td>1</td>
<td>( 4\pi \times 10^{-7} )</td>
</tr>
</tbody>
</table>

#### 4.4.1 Winding

A winding element provides the interface between the electric circuit and the magnetic equivalent circuit.

**Image:**

![Winding Element](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of Turns</td>
<td>No. of turns of the winding</td>
</tr>
<tr>
<td>Winding Resistance</td>
<td>Winding resistance, in Ohm</td>
</tr>
</tbody>
</table>

This element represents a winding on a magnetic core. The two electric nodes (\( E_1 \) and \( E_2 \)) are connected to an electric circuit, while the two magnetic nodes (\( M_1 \) and \( M_2 \)) are connected to other magnetic elements (such as leakage flux path, air gap, and magnetic core).
4.4.2 Leakage Flux Path

This element models the flow path of the leakage flux.

Image:

\[ M_1 \rightarrow \cdots \leftarrow M_2 \]

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inductance Factor ( A_L )</td>
<td>Inductance factor ( A_L ), in H, defined as the inductance per turn squared</td>
</tr>
<tr>
<td>Resistance for Losses</td>
<td>Resistance ( R ), in Ohm, that represents the losses due to the leakage flux.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag of the current that flows through the resistor ( R )</td>
</tr>
</tbody>
</table>

The resistance \( R \) represents the losses due to the leakage flux.

Assuming that the mmf (magnetomotive force) applied across the leakage flux path is \( F \), the electric equivalent circuit of the leakage flux path is as follows:

\[ M_1 \rightarrow \cdots \leftarrow M_2 \]

The mmf, in the form of a voltage source, applies across the capacitor (the capacitance is \( A_L \)) and the resistor \( R \). Let the current flowing through this branch be \( i \), and the rms value be \( I_{rms} \), the relationship between the losses due to the leakage flux and the resistance \( R \) is:

\[ P_{loss} = I_{rms}^2 \cdot R \]

4.4.3 Air Gap

The image and attributes of an air gap element are as follows.

Image:

\[ M_1 \rightarrow \cdots \leftarrow M_2 \]

The input parameters of the air gap can be defined in two ways. One is to define the air gap length and the cross section area, and the other is to define the inductance factor \( A_L \). They are as follows.

Attributes:

For the element Air Gap:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Air Gap Length</td>
<td>The length of the air gap, ( l_g ), in m</td>
</tr>
</tbody>
</table>
For the element \textit{Air Gap} (AL):

The resistance \( R \) represents the losses due to the air gap fringing effect. Assuming that the mmf (magnetomotive force) applied across the air gap is \( F \), the electric equivalent circuit of the air gap is as follows:

\[
\begin{align*}
+ & \\
\text{\( A_L \)} & \\
\text{\( F \)} & \\
\text{\( R \)} & \\
- & \\
\end{align*}
\]

The mmf, in the form of a voltage source, applies across the capacitor (the capacitance has the value of the inductance factor \( A_L \)) and the resistor \( R \). For the element \textit{Air Gap}, the inductance factor can be calculated from the air gap length and the cross section area as:

\[
A_L = \frac{\mu_o \cdot A_c}{L_g}
\]

where \( \mu_o = 4\pi \times 10^{-7} \).

The losses on the resistor represents the losses due to the fringing effect, which can be expressed as:

\[
P_{loss} = I_{rms}^2 \cdot R
\]

where \( I_{rms} \) is the rms value of the current \( i \) flowing through the resistor.

### 4.4.4 Linear Core

This element represents a linear loss less core.

\textbf{Image:}

\[
\begin{array}{c}
M_1 \\
\hline
\hline
\hline
M_2
\end{array}
\]

\textbf{Attributes:}

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inductance Factor ( A_L )</td>
<td>Inductance factor ( A_L ) of the core, in H, defined as the inductance per turn squared</td>
</tr>
</tbody>
</table>

If the length of the core is \( L_{length} \) and the cross section area is \( A_c \), the inductance factor \( A_L \) is expressed as:

\[
A_L = \frac{\mu_o \cdot \mu_r \cdot A_c}{L_{length}}
\]
where $\mu_r$ is the relative permeability of the core material.

### 4.4.5 Saturable Core

This element models a magnetic core with saturation and hysteresis.

**Image:**

![Diagram of a saturable core](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Inductance Factor $A_L$</td>
<td>Inductance factor $A_L$ of the core, in H, defined as the inductance per turn squared</td>
</tr>
<tr>
<td>Resistance for Losses</td>
<td>Resistance $R$, in Ohm, that represents the core losses</td>
</tr>
<tr>
<td>Coefficient phi_sat</td>
<td>Coefficient $\Phi_{sat}$ for the core B-H curve, in Weber</td>
</tr>
<tr>
<td>Coefficient $K_1$</td>
<td>Coefficient $K_1$ for the core B-H curve</td>
</tr>
<tr>
<td>Coefficient $K_{exp1}$</td>
<td>Coefficient $K_{exp1}$ for the core B-H curve</td>
</tr>
<tr>
<td>Coefficient $K_2$</td>
<td>Coefficient $K_2$ for the core B-H curve</td>
</tr>
<tr>
<td>Coefficient $K_{exp2}$</td>
<td>Coefficient $K_{exp2}$ for the core B-H curve</td>
</tr>
<tr>
<td>Initial Flux $\Phi_o$</td>
<td>Initial flux $\Phi_o$ of the core, in Weber</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag of the electric current that flows through the resistor $R$. If the rms value of the current is $I_{rms}$, the core losses can be calculated as: $P_{core_loss} = I_{rms}^2 * R$.</td>
</tr>
</tbody>
</table>

In the element image, the nodes $M_1$ and $M_2$ are the two nodes that connect the core to other magnetic elements (such as winding, flux leakage path, air gap, etc.). The node marked with a dot is Node $M_2$. Node $C_1$ is a control output node, which shows the flux (in Weber) flowing through the core, from Node $M_2$ to $M_1$.

The initial flux of the core, $\Phi_o$, is the flux flowing from Node $M_2$ to $M_1$ at the beginning, corresponding to the field intensity $H = 0$. The initial flux density $B_o$ can be calculated as: $B_o = \Phi_o / A_c$ (where $A_c$ is the core cross section area), and the initial mmf $F_o$ is: $F_o = \Phi_o / A_L$.

A differential voltage probe connected between Node $M_2$ to $M_1$ will measure the mmf (in ampere*turn) applied to the core.

The coefficients $\Phi_{sat}$, $K_1$, $K_{exp1}$, $K_2$, and $K_{exp2}$ are used to fit the B-H curve of an actual magnetic material. A good initial guess of $\Phi_{sat}$ is the maximum flux of the B-H curve in deep saturation. To calculate this flux, multiply the corresponding flux density $B$ by the cross section area of the core. Coefficient $K_1$ usually varies between 0.7 and 1, depending on the core material. Coefficient $K_{exp1}$ mainly affects the rate of the core saturation, and is in the range between 10 and 200 (10 for low permeability ferrite, and 200 for metglas).

The coefficients $K_2$ and $K_{exp2}$ are used in very rare occasions, such as for ferroresonant regulators. They are normally set as follows to keep them from affecting the B-H curve:

- $K_2 > 2$
- $K_{exp2} > 20$

A tutorial on how to define the core coefficients is provided in the "doc" sub-folder in the PSIM directory. Also, a program is provided to plot the B-H curve of the core given a set of coefficients. To launch this program, in PSIM, go to **Utilities >> B-H Curve**.
4.5 Other Elements

4.5.1 Operational Amplifier

Two types of operational amplifier (op. amp.) models are provided: ideal op. amp. model, and non-ideal op. amp. model (Level-1 model).

Note that the ideal op. amp. model works in the negative feedback mode but does not work in the positive feedback mode. The non-ideal op. amp. model does not have such a restriction.

4.5.1.1 Ideal Operational Amplifier


Images:

where

- \( V^+; V^- \) - noninverting and inverting input voltages
- \( V_o \) - output voltage
- \( A_o \) - op. amp. dc gain (\( A_o \) is set to 100,000.)
- \( R_o \) - output resistance (\( R_o \) is set to 80 Ohms)

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage ( V_{s+} )</td>
<td>Upper voltage source level of the op. amp.</td>
</tr>
<tr>
<td>Voltage ( V_{s-} )</td>
<td>Lower voltage source levels of the op. amp.</td>
</tr>
</tbody>
</table>

The difference between the element Op. Amp. and Op. Amp. (ground) or Op. Amp. (ground/inverted) is that, for the Op. Amp. element, the reference ground of the op. amp. model is connected to the power ground, whereas for Op. Amp. (ground) or Op. Amp. (ground/inverted), the reference ground node of the model is accessible and can be floating.

Note that the image of an op. amp. is similar to that of a comparator. For the op. amp., the inverting input is at the upper left and the noninverting input is at the lower left. For the comparator, it is the opposite.

**Example: A Boost Power Factor Correction Circuit**

The figure below shows a boost power factor correction circuit. The PI regulators of both the inner current loop and the outer voltage loop are implemented using op. amp.
4.5.1.2 Non-Ideal Operational Amplifier

As compared to the ideal op. amp. model, the non-ideal op. amp. model, also referred to as Level-1 op. amp. model, includes the following characteristics in the model:

- Op. amp. bandwidth
- Output current limit

The non-ideal op. amp. is modelled using power circuit elements, and similar to the ideal op. amp., is treated as a power element in PSIM.

Two non-ideal op. amp. elements are provided: *Op. Amp. (level-1)* and *Op. Amp. (ground) (level-1)*. The difference between these two elements is that, for *Op. Amp. (level-1)*, the reference ground of the op. amp. model is connected to the power ground, whereas for *Op. Amp. (ground) (level-1)*, the reference ground node of the model is accessible and can be floating.

The non-ideal op. amp. images have the number "1" at the upper right corner, as shown below.

**Images:**

<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1" alt="Non-Ideal Op. Amp. (level-1)" /></td>
<td><img src="image2" alt="Non-Ideal Op. Amp. (ground) (level-1)" /></td>
</tr>
</tbody>
</table>

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Input Resistance Rin</td>
<td>Input resistance of the op. amp., in Ohm</td>
</tr>
<tr>
<td>DC Gain $A_o$</td>
<td>DC gain of the op. amp.</td>
</tr>
<tr>
<td>Unit Gain Frequency</td>
<td>Frequency at which the op. amp. gain is 1, in Hz.</td>
</tr>
<tr>
<td>Output Resistance Ro</td>
<td>Output resistance of the op. amp., in Ohm</td>
</tr>
<tr>
<td>Maximum Output Current</td>
<td>Maximum current that the op. amp. output can provide, in A</td>
</tr>
<tr>
<td>Voltage $V_{s+}$</td>
<td>Upper voltage source level of the op. amp.</td>
</tr>
<tr>
<td>Voltage $V_{s-}$</td>
<td>Lower voltage source levels of the op. amp.</td>
</tr>
</tbody>
</table>

The figure below shows the definition of the dc gain $A_o$ and the unit gain frequency.
4.5.2 TL431 Shunt Regulator

The image of the TL431 shunt regulator is shown as below.

Image:

The TL431 regulator maintains the reference node voltage to be around 2.495V. In this model, the limited bandwidth of the TL431 is modelled. That is, the ac frequency response of the TL431 model resembles the following figure from the datasheet.

4.5.3 Opto-Coupler

The image and parameters of a opto-coupler are shown below.

Image:
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Current Transfer Ratio</td>
<td>The current transfer ratio $CTR$ between the transistor current $i_c$ and the diode current $i_d$, that is, $CTR = i_c/i_d$.</td>
</tr>
<tr>
<td>Diode Resistance</td>
<td>Diode resistance $R_d$, in Ohm. Note that the resistance must be greater than 0.</td>
</tr>
<tr>
<td>Diode Threshold Voltage</td>
<td>The forward diode threshold voltage $V_{d,th}$, in V</td>
</tr>
<tr>
<td>Transistor $V_{ce, sat}$</td>
<td>The transistor saturation voltage $V_{ce, sat}$, in V</td>
</tr>
<tr>
<td>Transistor-side Capacitance</td>
<td>Capacitance $C_p$ across the collector and emitter of the transistor, in F</td>
</tr>
</tbody>
</table>

These parameters can either be read directly from the manufacturer datasheet, or can be calculated from the datasheet information. Take the Motorola optocoupler 4N25 as an example. From the datasheet, we can read the current transfer ratio and the transistor saturation voltage as:

$CTR = 70\% = 0.7$; $V_{ce, sat} = 0.15$ V

From the "LED Forward Voltage versus Forward Current" characteristics on the datasheet, one can calculate the diode resistance $R_d$ and the threshold voltage $V_{d,th}$. We assume that the diode forward voltage is approximated by a straight line. That is,

$$v_d = V_{d,th} + R_d \cdot i_d$$

With $T_A = 25^\circ$C, we can obtain two readings from the curve: $i_d = 10$ mA and $v_d = 1.15$ V; $i_d = 40$ mA and $v_d = 1.3$ V. Based on these two points, we can calculate $R_d$ and $V_{d,th}$ as: $R_d = 5$ Ohm; $V_{d,th} = 1.1$ V.

The optocoupler model does not take into account the delay, but it does model the turn-on/turn-off transient through the capacitor $C_p$ across the collector and emitter of the transistor. The capacitance value can be obtained from the fall time $t_{fall}$ and the switching time test condition as:

$$C_p = \frac{t_{fall}}{2.2 \cdot R_L}$$

where $R_L$ is the load resistor in the switching time test circuit. For 4N25, for example, from the datasheet, we can obtain: $t_{fall} = 1.3$ $\mu$s, and $R_L = 100$ Ohm. The capacitance is calculated as: $C_p = 6$ nF.

4.5.4 dv/dt Block

A dv/dt block has the same function as the differentiator in the control circuit, except that it is for the power circuit.

Image:

![dv/dt block](image)

The output of the dv/dt block is equal to the derivative of the input voltage versus time. It is calculated as:

$$V_o = \frac{V_{in}(t) - V_{in}(t-\Delta t)}{\Delta t}$$

where $V_{in}(t)$ and $V_{in}(t-\Delta t)$ are the input values at the current and previous time step, and $\Delta t$ is the simulation time step.
4.5.5 Relays

Two relay blocks with one normally open (NO) switch and one normally closed (NC) switch are provided.

Images:

attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rated Coil Voltage</td>
<td>Rated voltage of the relay coil, in V</td>
</tr>
<tr>
<td>Coil Resistance</td>
<td>Resistance of the coil, in Ohm</td>
</tr>
<tr>
<td>Operate Voltage</td>
<td>Voltage at which the relay will operate, in V</td>
</tr>
<tr>
<td>Release Voltage</td>
<td>Voltage at which the relay will return to the default position, in V</td>
</tr>
<tr>
<td>Operate Time</td>
<td>Time from the moment the operate voltage is reached to the moment the switches operate, in sec.</td>
</tr>
<tr>
<td>Release Time</td>
<td>Time from the moment the release voltage is reached to the moment the switches return to the default positions, in sec.</td>
</tr>
</tbody>
</table>

The relays have one normally open switch and one normally closed switch. When a dc voltage is applied to the relay coil in the polarity as shown in the image, if the voltage reaches the Operate Voltage, after a time delay defined by the Operate Time, the NO switch will be closed, and the NC switch will be opened.

When the coil voltage reduces to the Release Voltage, after a time delay defined by the Release Time, the two switches will return to their default positions.

4.6 Motor Drive Module

The Motor Drive Module is an add-on module to the basic PSIM program. It provides machine models and mechanical load models for motor drive system studies.

The Motor Drive Module includes electric machines as described in this section, and mechanical elements and speed/torque/position sensors as described in Section 4.9.

4.6.1 Reference Direction of Mechanical Systems

In a motor drive system, in order to formulate equations for the mechanical system, a position notation needs to be defined. Take the following motor drive system as an example:

The system consists of two induction machines, IM1 and IM2, connected back-to-back. One operates as a motor, and the other as a generator. From the point of view of the first machine IM1, the mechanical equation can be written as:
where \( J_1 \) and \( J_2 \) are the moment of inertia, and \( T_{em1} \) and \( T_{em2} \) are the developed torques of the machine IM1 and IM2, respectively.

From the point of view of the second machine IM2, however, the mechanical equation can be written as:

\[
(J_1 + J_2) \frac{d\omega_m}{dt} = T_{em2} - T_{em1}
\]

These two equations are equally valid, but will produce opposite mechanical speed.

In order to avoid this ambiguity, in PSIM, the concept "reference direction" is used in the mechanical system so that the mechanical equation can be uniquely defined.

In a mechanical system, one element is designated as the master unit (this element is considered to operate in the master mode), and the rest of the elements are in the slave mode. Elements that can be master units are: Electric machines, mechanical-to-electrical interface blocks, and gear boxes.

The master unit defines the reference direction of the mechanical system. The direction is defined as the direction from the shaft node of the master unit, along the shaft, to the rest of the mechanical system.

Once the reference direction of the mechanical system is defined, the speed and torque reference of the mechanical system can be defined. For example, if we use the right-hand method, with the thumb pointing in the reference direction of the mechanical system, by rotating the right hand, the fingers will point to the positive direction of the speed and the torque.

Moreover, each mechanical element has its own reference direction. The following diagram shows the reference direction of each mechanical element, as indicated by the arrow:

The reference direction of each element and the reference direction of the overall mechanical system determine how the element interacts with the mechanical system.

For example, if the reference direction of a machine is along the same direction as the reference direction of the mechanical system, the developed torque of the machine will contribute to the shaft rotation in the positive direction. However, if the reference direction of the machine is opposite to that of the mechanical system, the developed torque will contribute to the shaft rotation in the negative direction.

In the two-machine example above, using the notation of the "reference direction", if we define the machine IM1 as the master unit, the reference direction of the overall mechanical system will be from left to right, as shown below. Based on this direction, the machine IM1 will be along the reference direction, and the machine IM2 will be opposite to the reference direction. This leads to the equivalent circuit of the mechanical system as
Similarly, if we define the machine IM2 as the master unit, the reference direction of the overall mechanical system will be from right to left, as shown below. Based on this direction, the machine IM1 will be opposite to the reference direction, and the machine IM2 will be along the reference direction. This leads to the equivalent circuit of the mechanical system as shown on the right.

The following shows another mechanical system with sensors and loads connected in different ways.

In this mechanical system, the machine on the left is the master unit. The reference direction of the mechanical system is from left to the right along the mechanical shaft. Comparing this direction with the reference direction of each element, Load 1, Speed Sensor 1, and Torque Sensor 1, will be along the reference direction, and Load 2, Speed Sensor 2, and Torque Sensor 2 will be opposite to the reference direction of the mechanical system.

Therefore, if the speed of the machine is positive, Speed Sensor 1 reading will be positive, and Speed Sensor 2 reading will be negative.

Similarly, the two constant-torque mechanical loads, with the amplitudes of $T_{L1}$ and $T_{L2}$, interact with the machine in different ways. Load 1 is along the reference direction, and the loading torque of Load 1 to the master machine will be $T_{L1}$. On the other hand, Load 2 is opposite to the reference direction, and the loading torque of Load 2 to the machine will be $-T_{L2}$.
4.6.2 Induction Machines

Linear and nonlinear models are provided for squirrel-cage and wound-rotor induction machines. The linear model is further divided into general type and symmetrical type. This section describes the linear models.

Four linear models are provided:
- Symmetrical 3-phase squirrel-cage induction machine
- General 3-phase squirrel-cage induction machine
- Symmetrical 3-phase wound-rotor induction machine
- General 3-phase wound-rotor induction machine

The images and parameters are shown as follows.

**Images:**

```
<table>
<thead>
<tr>
<th>Squirrel-cage</th>
<th>Squirrel-cage (with neutral)</th>
<th>Squirrel-cage (unconnected)</th>
</tr>
</thead>
<tbody>
<tr>
<td>IM</td>
<td>IM</td>
<td>IM</td>
</tr>
<tr>
<td>as</td>
<td>as</td>
<td>as+</td>
</tr>
<tr>
<td>bs</td>
<td>bs</td>
<td>bs+</td>
</tr>
<tr>
<td>cs</td>
<td>cs</td>
<td>bs-</td>
</tr>
<tr>
<td></td>
<td>ns</td>
<td>cs-</td>
</tr>
</tbody>
</table>
```

<table>
<thead>
<tr>
<th>Wound-rotor</th>
<th>Wound-rotor (unconnected)</th>
</tr>
</thead>
<tbody>
<tr>
<td>IM</td>
<td>IM</td>
</tr>
<tr>
<td>as</td>
<td>as</td>
</tr>
<tr>
<td>bs</td>
<td>bs</td>
</tr>
<tr>
<td>cs</td>
<td>cs</td>
</tr>
<tr>
<td>ns</td>
<td>ns</td>
</tr>
<tr>
<td>ar</td>
<td>ar</td>
</tr>
<tr>
<td>br</td>
<td>br</td>
</tr>
<tr>
<td>cr</td>
<td>cr</td>
</tr>
<tr>
<td>nr</td>
<td>nr</td>
</tr>
</tbody>
</table>

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$R_s$ (stator)</td>
<td>Stator winding resistance, in Ohm</td>
</tr>
<tr>
<td>$L_s$ (stator)</td>
<td>Stator winding leakage inductance, in H</td>
</tr>
<tr>
<td>$R_r$ (rotor)</td>
<td>Rotor winding resistance referred to the stator side, in Ohm</td>
</tr>
<tr>
<td>$L_r$ (rotor)</td>
<td>Rotor winding leakage inductance referred to the stator side, in H</td>
</tr>
<tr>
<td>$L_m$ (magnetizing)</td>
<td>Magnetizing inductance, in H</td>
</tr>
<tr>
<td>Ns/Nr Turns Ratio</td>
<td>Stator and rotor winding turns ratio (for wound-rotor machine only)</td>
</tr>
<tr>
<td>No. of Poles</td>
<td>Number of poles $P$ of the machine (an even integer)</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in $kg\cdot m^2$</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

All the parameters are referred to the stator side.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The models of the squirrel-cage induction machine with and without the neutral are the same internally.
The operation of a 3-phase induction machine is described by the following equations:

\[
\begin{bmatrix}
v_{abc, s} \\
v_{abc, r}
\end{bmatrix} = \begin{bmatrix}
R_s & 0 & 0 \\
0 & R_s & 0 \\
0 & 0 & R_r
\end{bmatrix}
\begin{bmatrix}
i_{abc, s} \\
i_{abc, r}
\end{bmatrix} + \begin{bmatrix}
L_s & M_{sr} & -M_{sr} \\
-M_{sr} & L_s + M_{sr} & -M_{sr} \\
-M_{sr} & -M_{sr} & L_r + M_{sr}
\end{bmatrix}
\begin{bmatrix}
di_{abc, s} \\
di_{abc, r}
\end{bmatrix} + \begin{bmatrix}
0 \\
\frac{d}{dt}i_{abc, r}
\end{bmatrix}
\]

where

\[
\begin{bmatrix}
v_{abc, s} \\
v_{abc, r}
\end{bmatrix} = \begin{bmatrix}
v_{a, s} \\
v_{b, s} \\
v_{c, s}
\end{bmatrix}, \quad \begin{bmatrix}
v_{abc, r}
\end{bmatrix} = \begin{bmatrix}
v_{a, r} \\
v_{b, r} \\
v_{c, r}
\end{bmatrix}, \quad \begin{bmatrix}
i_{abc, s}
\end{bmatrix} = \begin{bmatrix}
i_{a, s} \\
i_{b, s} \\
i_{c, s}
\end{bmatrix}, \quad \begin{bmatrix}
i_{abc, r}
\end{bmatrix} = \begin{bmatrix}
i_{a, r} \\
i_{b, r} \\
i_{c, r}
\end{bmatrix}
\]

For squirrel-cage machines, \(v_{a,r} = v_{b,r} = v_{c,r} = 0\). The parameter matrices are defined as:

\[
\begin{aligned}
\begin{bmatrix}
R_s & 0 & 0 \\
0 & R_s & 0 \\
0 & 0 & R_r
\end{bmatrix} &= \begin{bmatrix}
R_s & 0 & 0 \\
0 & R_r & 0 \\
0 & 0 & R_r
\end{bmatrix} \\
\begin{bmatrix}
L_s + M_{sr} & -M_{sr} & -M_{sr} \\
-M_{sr} & L_s + M_{sr} & -M_{sr} \\
-M_{sr} & -M_{sr} & L_r + M_{sr}
\end{bmatrix} &= \begin{bmatrix}
L_r + M_{sr} & -M_{sr} & -M_{sr} \\
-M_{sr} & L_r + M_{sr} & -M_{sr} \\
-M_{sr} & -M_{sr} & L_r + M_{sr}
\end{bmatrix}
\end{aligned}
\]

\[
\begin{bmatrix}
M_{sr} \\
M_{sr} \\
M_{sr}
\end{bmatrix} = M_{sr} \begin{bmatrix}
\cos \theta & \cos(\theta + \frac{2\pi}{3}) & \cos(\theta - \frac{2\pi}{3}) \\
\cos(\theta - \frac{2\pi}{3}) & \cos \theta & \cos(\theta + \frac{2\pi}{3}) \\
\cos(\theta + \frac{2\pi}{3}) & \cos(\theta - \frac{2\pi}{3}) & \cos \theta
\end{bmatrix}
\]

where \(M_{sr}\) is the mutual inductance between the stator and rotor windings, and \(\theta\) is the mechanical angle. The mutual inductance is related to the magnetizing inductance as:

\[
L_m = \frac{3}{2} M_{sr}
\]

The mechanical equation is expressed as:

\[
J \cdot \frac{d\omega_m}{dt} = T_{em} - T_L
\]

where the developed torque \(T_{em}\) is defined as:

\[
T_{em} = \frac{P}{2} \begin{bmatrix}
i_{abc, s}
\end{bmatrix}^T \frac{d}{d\theta} \begin{bmatrix}
M_{sr}
\end{bmatrix} \cdot \begin{bmatrix}
i_{abc, r}
\end{bmatrix}
\]

For a symmetrical squirrel-cage induction machine, the steady state equivalent circuit is shown below. In the figure, \(s\) is the slip.
Example: A VSI Induction Motor Drive System

The figure below shows an open-loop induction motor drive system. The motor has 6 poles and is fed by a voltage source inverter with sinusoidal PWM. The dc bus is fed through a diode bridge.

The simulation waveforms of the mechanical speed (in rpm), developed torque $T_{em}$ and load torque $T_{load}$, and 3-phase input currents show the start-up transient.

4.6.3 Induction Machine with Saturation

Two models of induction machines with saturation are provided:
- 3-phase squirrel-cage induction machine
- 3-phase wound-rotor induction machine

Images:
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$R_s$ (stator)</td>
<td>Stator winding resistance, in Ohm</td>
</tr>
<tr>
<td>$L_s$ (stator)</td>
<td>Stator winding leakage inductance, in H</td>
</tr>
<tr>
<td>$R_r$ (rotor)</td>
<td>Rotor winding resistance referred to the stator side, in Ohm</td>
</tr>
<tr>
<td>$L_r$ (rotor)</td>
<td>Rotor winding leakage inductance referred to the stator side, in H</td>
</tr>
<tr>
<td>$N_s/N_r$</td>
<td>Stator and rotor winding turns ratio (for wound-rotor machine only)</td>
</tr>
<tr>
<td>No. of Poles</td>
<td>Number of poles $P$ of the machine (an even integer)</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in kg*m$^2$</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
<tr>
<td>$I_m$ vs. $L_m$ $(I_{m1},L_{m1})$ ...</td>
<td>Characteristics of the magnetizing current $I_m$ versus the magnetizing inductance $[(I_{m1},L_{m1}) (I_{m2},L_{m2}) ...]$ where $I_m$ is in A and $L_m$ is in H.</td>
</tr>
</tbody>
</table>

All the parameters are referred to the stator side.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The operation of a 3-phase induction machine with saturation is described by the following equations:

$$
\begin{align*}
    \dot{v}_{abc,1} &= \left[ R_s \cdot \begin{bmatrix} 1 \\ -1/2 \\ 1/2 \end{bmatrix} + L_s \cdot \frac{d}{dt} \begin{bmatrix} i_{abc,1} \\ i_{abc,2} \\ i_{abc,3} \end{bmatrix} + \frac{d}{dt} [\lambda_{abc,s}] \right] \\
    \dot{v}_{abc,2} &= \left[ R_s \cdot \begin{bmatrix} 1 \\ -1/2 \\ 1/2 \end{bmatrix} + L_r \cdot \frac{d}{dt} \begin{bmatrix} i_{abc,1} \\ i_{abc,2} \\ i_{abc,3} \end{bmatrix} + \frac{d}{dt} [\lambda_{abc,r}] \right]
\end{align*}
$$

where

$$
\begin{align*}
    [\lambda_{abc,s}] &= M_{sr} \cdot \begin{bmatrix} 1 \\ -1/2 \\ 1/2 \end{bmatrix} \cdot [\lambda_{abc,1}] + M_{sr} \cdot \begin{bmatrix} \cos \theta & \cos(\theta + \frac{2\pi}{3}) & \cos(\theta - \frac{2\pi}{3}) \\ \cos(\theta - \frac{2\pi}{3}) & \cos \theta & \cos(\theta + \frac{2\pi}{3}) \\ \cos(\theta + \frac{2\pi}{3}) & \cos(\theta - \frac{2\pi}{3}) & \cos \theta \end{bmatrix} \cdot [\lambda_{abc,2}] \\
    [\lambda_{abc,r}] &= M_{sr} \cdot \begin{bmatrix} \cos \theta & \cos(\theta - \frac{2\pi}{3}) & \cos(\theta + \frac{2\pi}{3}) \\ \cos(\theta + \frac{2\pi}{3}) & \cos \theta & \cos(\theta - \frac{2\pi}{3}) \\ \cos(\theta - \frac{2\pi}{3}) & \cos(\theta + \frac{2\pi}{3}) & \cos \theta \end{bmatrix} \cdot [\lambda_{abc,1}] + M_{sr} \cdot \begin{bmatrix} 1 \\ -1/2 \\ 1/2 \end{bmatrix} \cdot \begin{bmatrix} 1/2 \\ -1/2 \\ 1/2 \end{bmatrix}
\end{align*}
$$

In this case, the inductance $M_{sr}$ is no longer constant, but a function of the magnetizing current $I_m$. The magnetizing current $I_m$ and inductance $L_m$ are defined by a series of data points in pair, for example, "(0, 0.041) (5, 0.035) (20, 0.03)". Between two data points, the inductance $L_m$ is interpolated linearly. When the magnetizing current is less than the minimum or greater than the maximum, the inductance will be clamped to the value at the first point or the last point.
4.6.4  DC Machine

The image and parameters of a dc machine are as follows:

**Image:**

![Image of a DC machine with armature and field windings connected to a shaft node.]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$R_a$ (armature)</td>
<td>Armature winding resistance, in Ohm</td>
</tr>
<tr>
<td>$L_a$ (armature)</td>
<td>Armature winding inductance, in H</td>
</tr>
<tr>
<td>$R_f$ (field)</td>
<td>Field winding resistance, in Ohm</td>
</tr>
<tr>
<td>$L_f$ (field)</td>
<td>Field winding inductance, in H</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the machine, in kg*m$^2$</td>
</tr>
<tr>
<td>$V_t$ (rated)</td>
<td>Rated armature terminal voltage, in V</td>
</tr>
<tr>
<td>$I_a$ (rated)</td>
<td>Rated armature current, in A</td>
</tr>
<tr>
<td>$n$ (rated)</td>
<td>Rated mechanical speed, in rpm</td>
</tr>
<tr>
<td>$I_f$ (rated)</td>
<td>Rated field current, in A</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>The master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

When the torque flag is set to 1, the internal torque generated by the machine will be saved to the output file for display.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The operation of a dc machine is described by the following equations:

\[ v_t = E_a + i_a \cdot R_a + L_a \frac{di_a}{dt} \]

\[ v_f = i_f \cdot R_f + L_f \frac{di_f}{dt} \]

\[ E_a = k \cdot \phi \cdot \omega_m \]

\[ T_{em} = k \cdot \phi \cdot i_a \]

\[ J \cdot \frac{d\omega_m}{dt} = T_{em} - T_L \]

where $v_t$, $v_f$, $i_a$, and $i_f$ are the armature and field winding voltage and current, respectively; $E_a$ is the back emf,
\( \omega_m \) is the mechanical speed in rad./sec., \( T_{em} \) is the internal developed torque, and \( T_L \) is the load torque. The back emf and the internal torque can also be expressed as:

\[
E_a = L_{af} \cdot i_f \cdot \omega_m
\]

\[
T_{em} = L_{af} \cdot i_f \cdot i_a
\]

where \( L_{af} \) is the mutual inductance between the armature and the field windings. It can be calculated based on the rated operating conditions as:

\[
L_{af} = \frac{(V_i - I_a \cdot R_a)}{I_f \cdot \omega_m}
\]

Note that the dc machine model assumes magnetic linearity. Saturation is not considered.

**Example: A DC Motor with a Constant-Torque Load**

The circuit below shows a shunt-excited dc motor with a constant-torque load \( T_L \). Since the load is along the reference direction of the mechanical system, the loading torque to the machine is \( T_L \). Also, the speed sensor is along the reference direction. It will give a positive output for a positive speed.

The simulation waveforms of the armature current and the speed are shown on the right.

### 4.6.5 Brushless DC Machine

A 3-phase brushless dc machine is a type of permanent magnet synchronous machine with trapezoidal waveform back emf. It has 3-phase windings on the stator, and permanent magnet on the rotor.

The image of the 3-phase brushless dc machine is shown below. Two types of parameter inputs are provided: One based on machine model parameters, and the other based on manufacturer datasheet information.

**Attributes** based on machine model parameters:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R ) (stator resistance)</td>
<td>Stator phase resistance ( R ), in Ohm</td>
</tr>
<tr>
<td>( L ) (stator self ind.)</td>
<td>Stator phase self inductance ( L ), in H</td>
</tr>
</tbody>
</table>
### Attributes based on manufacturer datasheet information:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance (phase-phase)</td>
<td>Phase-to-phase (or line-to-line) resistance, in Ohm</td>
</tr>
<tr>
<td>Inductance (phase-phase)</td>
<td>Phase-to-phase (or line-to-line) inductance, in H</td>
</tr>
<tr>
<td>Speed Constant</td>
<td>Speed constant $K_v$, defined as the ratio between the speed and the applied voltage, in rpm/V</td>
</tr>
<tr>
<td>Torque Constant</td>
<td>Torque constant $K_t$, defined as the ratio between the generated torque and the applied current, in N*m/A</td>
</tr>
<tr>
<td>No. of Poles P</td>
<td>Number of poles $P$</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in kg*m$^2$</td>
</tr>
<tr>
<td>No Load Speed</td>
<td>The motor speed at no load with the nominal voltage applied, in rpm</td>
</tr>
</tbody>
</table>

**$M$ (stator mutual ind.)**
Stator mutual inductance $M$, in H
The mutual inductance $M$ is a negative value. Depending on the winding structure, the ratio between $M$ and the stator self inductance $L$ is normally between $-1/3$ and $-1/2$. If $M$ is unknown, a reasonable value of $M$ equal to $-0.4 \times L$ can be used as the default value.

**Vpk / krpm**
Peak line-to-line back emf constant, in V/krpm (mechanical speed)

**Vrms / krpm**
RMS line-to-line back emf constant, in V/krpm (mechanical speed).
The values of Vpk/krpm and Vrms/krpm should be available from the machine data sheet. If these values are not available, they can be obtained through experiments by operating the machine as a generator at 1000 rpm and measuring the peak and rms values of the line-to-line voltage.

**No. of Poles $P$**
Number of poles $P$

**Moment of Inertia**
Moment of inertia $J$ of the machine, in kg*m$^2$

**Shaft Time Constant**
Shaft time constant $\tau_{\text{shaft}}$

**theta_0 (deg.)**
Initial rotor angle $\theta_0$ in electrical deg.
The initial rotor angle is the rotor angle at $t=0$. The zero rotor angle position is defined as the position where Phase A back emf crosses zero (from negative to positive) under a positive rotation speed.

**theta_advance (deg.)**
Position sensor advance angle $\theta_{\text{advance}}$ in electrical deg.
The advance angle is defined as such that, for a brushless dc machine with a 120° trapezoidal back emf waveform, if the advance angle is 0, the leading edge of the Phase A hall effect sensor signal will align with the intersection of the rising ramp and the flat-top of the back emf trapezoidal waveform.

**Conduction Pulse Width**
Position sensor conduction pulse width, in electrical deg.
Positive conduction pulse can turn on the upper switch and negative pulse can turn on the lower switch in a full bridge inverter. The conduction pulse width is 120 electrical deg. for 120° conduction mode.

**Torque Flag**
Output flag for internal developed torque $T_{em}$

**Master/Slave Flag**
Master/slave flag of the machine (1: master; 0: slave)
The node assignments of the image are: Nodes a, b, and c are the stator winding terminals for Phase A, B, and C, respectively. The stator windings are Y connected, and Node n is the neutral point. The shaft node is the connecting terminal for the mechanical shaft. They are all power nodes and should be connected to the power circuit.

Node sa, sb, and sc are the outputs of the built-in 6-pulse hall effect position sensors for Phase A, B, and C, respectively. The sensor output is a bipolar commutation pulse (1, 0, and -1). The sensor output nodes are all control nodes and should be connected to the control circuit.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The equations of the 3-phase brushless dc machine are:

\[
\begin{align*}
va & = R_i a \cdot \frac{di_a}{dt} + E_a \\
vb & = R_i b \cdot \frac{di_b}{dt} + E_b \\
vc & = R_i c \cdot \frac{di_c}{dt} + E_c
\end{align*}
\]

where \(v_a, v_b, \) and \(v_c\) are the phase voltages, \(i_a, i_b, \) and \(i_c\) are the phase currents, \(R, L, \) and \(M\) are the stator phase resistance, self inductance, and mutual inductance, and \(E_a, E_b, \) and \(E_c\) are the back emf of Phase A, B, and C, respectively.

The back emf voltages are a function of the rotor mechanical speed \(\omega_m\) and the rotor electrical angle \(\theta_r\), that is:

\[
\begin{align*}
E_a & = k_{e_a} \cdot \omega_m \\
E_b & = k_{e_b} \cdot \omega_m \\
E_c & = k_{e_c} \cdot \omega_m
\end{align*}
\]

The coefficients \(k_{e_a}, k_{e_b}, \) and \(k_{e_c}\) are dependent on the rotor angle \(\theta_r\). In this model, an ideal trapezoidal waveform profile is assumed, as shown below for Phase A. Also shown is the Phase A hall effect sensor signal \(S_a\).

where \(K_{pk}\) is the peak trapezoidal value, in V/(rad./sec.), which is defined as: \(K_{pk} = \frac{V_{pk}}{krpm} \cdot \frac{1}{1000 \cdot \frac{2\pi}{60}}\).

Given the values of Vpk/krpm and Vrms/krpm, the angle \(\alpha\) is determined automatically in the program.

The developed torque of the machine is:

\[
T_{em} = \frac{(E_a \cdot i_a + E_b \cdot i_b + E_c \cdot i_c)}{\omega_m}
\]

The mechanical equations are:
where \( B \) is the friction coefficient, \( T_{load} \) is the load torque, and \( P \) is the number of poles. The coefficient \( B \) is calculated from the moment of inertia \( J \) and the shaft time constant \( \tau_{shaft} \) as below:

\[
B = \frac{J}{\tau_{shaft}}
\]

The shaft time constant \( \tau_{shaft} \) therefore reflects the effect of the friction and windage of the machine. Note that when the shaft time constant is set to 0, the friction term is \( B \omega_m \) is ignored.

To better understand the definition of the shaft time constant, we can represent the mechanical equation with the following equivalent circuit:

![Equivalent Circuit Diagram]

This circuit shows that the shaft time constant \( \tau_{shaft} \) is equal to the RC time constant of the resistor \( 1/B \) and the capacitor \( J \). Therefore, the shaft time constant can be measured by the following test:

- Connect the machine to an external mechanical source. With the stator side in open circuit, drive the machine to a certain speed.
- Remove the mechanical source. The shaft time constant will be equal to the time that it takes the machine to decelerate to 36.8% of its initial speed.

More Explanation on the Hall Effect Sensor:

A hall effect position sensor consists of a set of hall switches and a set of trigger magnets.

The hall switch is a semiconductor switch (e.g. MOSFET or BJT) that opens or closes when the magnetic field is higher or lower than a certain threshold value. It is based on the hall effect, which generates an emf proportional to the flux-density when the switch is carrying a current supplied by an external source. It is common to detect the emf using a signal conditioning circuit integrated with the hall switch or mounted very closely to it. This provides a TTL-compatible pulse with sharp edges and high noise immunity for connection to the controller via a screened cable. For a three-phase brushless dc motor, three hall switches are spaced 120 electrical deg. apart and are mounted on the stator frame.

The set of trigger magnets can be a separate set of magnets, or it can use the rotor magnets of the brushless motor. If the trigger magnets are separate, they should have the matched pole spacing (with respect to the rotor magnets), and should be mounted on the shaft in close proximity to the hall switches. If the trigger magnets use the rotor magnets of the machine, the hall switches must be mounted close enough to the rotor magnets, where they can be energized by the leakage flux at the appropriate rotor positions.

Example: Defining Brushless DC Motor Parameters from Manufacturer Datasheet

This example illustrates how to define brushless dc motor parameters from manufacturer datasheet. Below is the information provided on the datasheet of the brushless dc motor Maxon EC-22-16730 (32V, 50W) from Maxon Motor.

<table>
<thead>
<tr>
<th>Values at nominal voltage</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Nominal voltage (V)</td>
<td>32</td>
</tr>
<tr>
<td>No load speed (rpm)</td>
<td>38700</td>
</tr>
<tr>
<td>No load current (mA)</td>
<td>327</td>
</tr>
</tbody>
</table>
Characteristics
- Terminal resistance phase to phase (Ohm) 0.363
- Terminal inductance phase to phase (mH) 0.049
- Torque constant (mNm/A) 7.85
- Speed constant (rpm/V) 1220
- Rotor inertia (gcm²) 4.2

Other specifications:
- Number of pole pairs 1
- Number of phases 3

Using the element based on manufacturer datasheet information, and after converting all the quantities to the SI units, the motor parameters in PSIM are defined as follows:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance (phase-phase)</td>
<td>0.363</td>
</tr>
<tr>
<td>Inductance (phase-phase)</td>
<td>0.049m</td>
</tr>
<tr>
<td>Speed Constant</td>
<td>1220</td>
</tr>
<tr>
<td>Torque Constant</td>
<td>7.85m</td>
</tr>
<tr>
<td>No. of Poles P</td>
<td>2</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>4.2e-7</td>
</tr>
<tr>
<td>No Load Speed</td>
<td>38700</td>
</tr>
<tr>
<td>No Load Current</td>
<td>327m</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>1</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>1</td>
</tr>
</tbody>
</table>

Example: Start-Up of an Open-Loop Brushless DC Motor

The figure below shows an open-loop brushless dc motor drive system. The motor is fed by a 3-phase voltage source inverter. The outputs of the motor hall effect position sensors are used as the gating signals for the inverter, resulting a 6-pulse operation.

The simulation waveforms show the start-up transient of the mechanical speed (in rpm), developed torque $T_{em}$, and 3-phase input currents.

4.6.6 Synchronous Machine with External Excitation

The structure of a conventional synchronous machine consists of three stator windings, one field winding on either a salient or cylindrical rotor, and an optional damping winding on the rotor.

Depending on the way the internal model interfaces with the external stator circuitry, there are two types of interface: one is the voltage-type interface, and the other is the current-type interface. The model for the voltage-type interface consists of controlled voltage sources on the stator side, and this model is suitable in
situations where the machine operates as a generator and/or the stator external circuit is in series with inductive branches. On the other hand, The model for the current-type interface consists of controlled current sources on the stator side, and this model is suitable in situations where the machine operates as a motor and/or the stator external circuit is in parallel with capacitive branches.

The image and parameters of the machine are shown as follows.

### Image:

![Image of a synchronous machine with a shaft node and field connections](image)

### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_s ) (stator)</td>
<td>Stator winding resistance, in Ohm</td>
</tr>
<tr>
<td>( L_s ) (stator)</td>
<td>Stator leakage inductance, in H</td>
</tr>
<tr>
<td>( L_{dm} ) (d-axis mag. ind.)</td>
<td>d-axis magnetizing inductance, in H</td>
</tr>
<tr>
<td>( L_{qm} ) (q-axis mag. ind.)</td>
<td>q-axis magnetizing inductance, in H.</td>
</tr>
<tr>
<td>( R_f ) (field)</td>
<td>Field winding resistance referred to the stator side, in Ohm</td>
</tr>
<tr>
<td>( L_{fl} ) (field leakage ind.)</td>
<td>Field winding leakage inductance referred to the stator side, in H.</td>
</tr>
<tr>
<td>( R_{dr} ) (damping cage)</td>
<td>Rotor damping cage d-axis resistance referred to the stator side, in Ohm</td>
</tr>
<tr>
<td>( L_{drl} ) (damping cage)</td>
<td>Rotor damping cage d-axis leakage inductance referred to the stator side, in H</td>
</tr>
<tr>
<td>( R_{qr} ) (damping cage)</td>
<td>Rotor damping cage q-axis resistance referred to the stator side, in Ohm</td>
</tr>
<tr>
<td>( L_{qrl} ) (damping cage)</td>
<td>Rotor damping cage q-axis leakage inductance referred to the stator side, in H</td>
</tr>
<tr>
<td>( N_s/N_f ) (effective)</td>
<td>Stator-field winding effective turns ratio</td>
</tr>
<tr>
<td>Number of Poles ( P )</td>
<td>Number of Poles ( P )</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia ( J ) of the machine, in kg*m^2</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal developed torque ( T_{em} )</td>
</tr>
<tr>
<td>Master/slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

All the parameters are referred to the stator side.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The equations of the synchronous machine can be expressed as follows:

\[
\begin{bmatrix}
\dot{\vec{I}} \\
\end{bmatrix} = \begin{bmatrix}
\vec{R} \\
\end{bmatrix} \cdot \begin{bmatrix}
\vec{I} \\
\end{bmatrix} + \frac{d}{dt} \begin{bmatrix}
\vec{H} \\
\end{bmatrix}
\]

where

\[
\begin{bmatrix}
\vec{I} \\
\end{bmatrix} = \begin{bmatrix}
v_a & v_b & v_c & v_f & 0 \\
\end{bmatrix}^T \quad \begin{bmatrix}
\vec{H} \\
\end{bmatrix} = \begin{bmatrix}
i_d & i_b & i_c & i_f & i_{dr} & i_{qr} \\
\end{bmatrix}^T
\]
\[
\mathbf{R} = \text{diag} \begin{bmatrix} R_s & R_s & R_s & R_f & R_{dr} & R_{qg} \end{bmatrix} \quad \mathbf{\lambda} = \begin{bmatrix} \lambda_a & \lambda_b & \lambda_c & \lambda_{dr} & \lambda_{qg} \end{bmatrix}^T
\]
and \([\mathbf{\lambda}] = [L]^*[I].\) The inductance matrix is defined as follows:
\[
\mathbf{L} = \begin{bmatrix} L_{11} & L_{12} \\ L_{12}^T & L_{22} \end{bmatrix}
\]
and
\[
L_{11} = \begin{bmatrix}
L_s + L_o + L_2 \cos(2\theta_r) & -\frac{L_o}{2} + L_2 \cos\left(2\theta_r - \frac{2\pi}{3}\right) & -\frac{L_o}{2} + L_2 \cos\left(2\theta_r + \frac{2\pi}{3}\right) \\
-\frac{L_o}{2} + L_2 \cos\left(2\theta_r - \frac{2\pi}{3}\right) & L_s + L_o + L_2 \cos(2\theta_r) & -\frac{L_o}{2} + L_2 \cos(2\theta_r) \\
-\frac{L_o}{2} + L_2 \cos\left(2\theta_r + \frac{2\pi}{3}\right) & -\frac{L_o}{2} + L_2 \cos(2\theta_r) & L_s + L_o + L_2 \cos\left(2\theta_r - \frac{2\pi}{3}\right)
\end{bmatrix}
\]
\[
L_{12} = \begin{bmatrix}
L_{sf} \cos(2\theta_r) & L_{sa} \cos(2\theta_r) & -L_{sq} \sin(2\theta_r) \\
L_{sf} \cos\left(2\theta_r - \frac{2\pi}{3}\right) & L_{sa} \cos\left(2\theta_r - \frac{2\pi}{3}\right) & -L_{sq} \sin\left(2\theta_r - \frac{2\pi}{3}\right) \\
L_{sf} \cos\left(2\theta_r + \frac{2\pi}{3}\right) & L_{sa} \cos\left(2\theta_r + \frac{2\pi}{3}\right) & -L_{sq} \sin\left(2\theta_r + \frac{2\pi}{3}\right)
\end{bmatrix}
\]
\[
L_{22} = \begin{bmatrix}
L_f & L_{fdr} & 0 \\
L_{fdr} & L_{dr} & 0 \\
0 & 0 & L_{qg}
\end{bmatrix}
\]
where \(\theta_r\) is the rotor angle.

The developed torque can be expressed as:
\[
T = \frac{P}{2} \cdot \mathbf{L} \cdot \frac{d}{d\theta_r} [I] \cdot [I]
\]

The mechanical equations are:
\[
J \frac{d\omega_m}{dt} = T_{em} - T_{load}
\]
\[
\frac{d\theta_r}{dt} = \frac{P}{2} \cdot \omega_m
\]

The input parameters and the parameters in the equations are related in the following way:
\[
L_{dm} = 1.5 \cdot (L_o + L_2)
\]
\[
L_{qm} = 1.5 \cdot (L_o - L_2)
\]
\[
L_{sf} = \left(\frac{N_f}{N_s}\right)^2 \cdot L_{dm}
\]
\[
L_{sd} = L_{dm}
\]
\[
L_{sq} = L_{qm}
\]
\[
L_{fi} = L_f - L_{sf}
\]
\[
L_{fdr} = L_{dm}
\]
4.6.7 Permanent Magnet Synchronous Machine

A 3-phase permanent magnet synchronous machine has 3-phase windings on the stator, and permanent magnet on the rotor. The difference between this machine and the brushless dc machine is that the machine back emf is sinusoidal.

The image and parameters of the machine are shown as follows.

Image:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_s ) (stator resistance)</td>
<td>Stator winding resistance, in Ohm</td>
</tr>
<tr>
<td>( L_d ) (d-axis ind.)</td>
<td>Stator d-axis inductance, in H</td>
</tr>
<tr>
<td>( L_q ) (q-axis ind.)</td>
<td>Stator q-axis inductance, in H.</td>
</tr>
<tr>
<td>( V_{pk} / \text{krpm} )</td>
<td>Peak line-to-line back emf constant, in V/krpm (mechanical speed). The value of ( V_{pk}/\text{krpm} ) should be available from the machine data sheet. If this data is not available, it can be obtained through an experiment by operating the machine as a generator at 1000 rpm and measuring the peak line-to-line voltage.</td>
</tr>
<tr>
<td>No. of Poles ( P )</td>
<td>Number of poles ( P )</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia ( J ) of the machine, in kg*m²</td>
</tr>
<tr>
<td>Shaft Time Constant</td>
<td>Shaft time constant ( \tau_{\text{shaft}} )</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal developed torque ( T_{em} )</td>
</tr>
<tr>
<td>Master/slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

The node assignments of the image are: Nodes \( a \), \( b \), and \( c \) are the stator winding terminals for Phase \( a \), \( b \), and \( c \), respectively. The stator windings are Y connected, and Node \( n \) is the neutral point. The shaft node is the connecting terminal for the mechanical shaft. They are all power nodes and should be connected to the power circuit.

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The equations of the permanent-magnet synchronous machine are:

\[
L_{drl} = L_{dr} - L_{dm}
\]
\[
L_{qrl} = L_{qr} - L_{qm}
\]
where $v_a$, $v_b$, $v_c$, and $i_a$, $i_b$, and $i_c$, and $\lambda_a$, $\lambda_b$, $\lambda_c$ are the stator phase voltages, currents, and flux linkages, respectively, and $R_s$ is the stator phase resistance. The flux linkages are further defined as:

$$\lambda = \begin{bmatrix} \lambda_a \\ \lambda_b \\ \lambda_c \end{bmatrix} = \begin{bmatrix} L_{aa} & L_{ab} & L_{ac} \\ L_{ba} & L_{bb} & L_{bc} \\ L_{ca} & L_{cb} & L_{cc} \end{bmatrix} \cdot \begin{bmatrix} i_a \\ i_b \\ i_c \end{bmatrix} + \lambda_{pm} \cdot \begin{bmatrix} \cos(\theta_r) \\ \cos(\theta_r - \frac{2\pi}{3}) \\ \cos(\theta_r + \frac{2\pi}{3}) \end{bmatrix}$$

where $\theta_r$ is the rotor electrical angle, and $\lambda_{pm}$ is the peak stator phase flux linkage defined as:

$$\lambda_{pm} = \frac{60 \cdot V_{pk}/krpm}{\sqrt{3} \cdot \pi \cdot P \cdot 1000}$$

where $P$ is the number of poles.

The stator self and mutual inductances are rotor position dependent, and are defined as:

$$L_{aa} = L_s + L_a + L_2 \cdot \cos(2\theta_r)$$
$$L_{bb} = L_s + L_a + L_2 \cdot \cos\left(2\theta_r + \frac{2\pi}{3}\right)$$
$$L_{cc} = L_s + L_a + L_2 \cdot \cos\left(2\theta_r - \frac{2\pi}{3}\right)$$
$$L_{ab} = -\frac{L_a}{2} + L_2 \cdot \cos\left(2\theta_r - \frac{2\pi}{3}\right)$$
$$L_{ac} = -\frac{L_a}{2} + L_2 \cdot \cos\left(2\theta_r + \frac{2\pi}{3}\right)$$
$$L_{bc} = L_{cb} = -\frac{L_a}{2} + L_2 \cdot \cos(2\theta_r)$$

where $L_s$ is the stator leakage inductance. The variables in the abc frame can be converted to the dq0 frame using the following transformation:

$$\begin{bmatrix} x_d \\ x_q \end{bmatrix} = \frac{2}{3} \cdot \begin{bmatrix} \cos(\theta_r) & \cos\left(\theta_r - \frac{2\pi}{3}\right) & \cos\left(\theta_r + \frac{2\pi}{3}\right) \\ -\sin(\theta_r) & -\sin\left(\theta_r - \frac{2\pi}{3}\right) & -\sin\left(\theta_r + \frac{2\pi}{3}\right) \end{bmatrix} \cdot \begin{bmatrix} x_a \\ x_b \\ x_c \end{bmatrix}$$

The inverse transformation is as follows:

$$\begin{bmatrix} x_a \\ x_b \\ x_c \end{bmatrix} = \begin{bmatrix} \cos(\theta_r) & -\sin(\theta_r) & 1 \\ \cos\left(\theta_r - \frac{2\pi}{3}\right) & -\sin\left(\theta_r - \frac{2\pi}{3}\right) & 1 \\ \cos\left(\theta_r + \frac{2\pi}{3}\right) & -\sin\left(\theta_r + \frac{2\pi}{3}\right) & 1 \end{bmatrix} \cdot \begin{bmatrix} x_d \\ x_q \end{bmatrix}$$
The d-axis and q-axis inductances are associated with the inductances in the abc frame as follows:

\[ L_d = L_s + \frac{3}{2}L_o + \frac{3}{2}L_2 \]
\[ L_q = L_s + \frac{3}{2}L_o - \frac{3}{2}L_2 \]

The developed torque can be expressed as:

\[ T_{em} = -\frac{P}{2} \cdot L_2 \cdot \begin{bmatrix} \sin(2\theta_r) & \sin\left(2\theta_r - \frac{2\pi}{3}\right) & \sin\left(2\theta_r + \frac{2\pi}{3}\right) \\ \sin\left(2\theta_r - \frac{2\pi}{3}\right) & \sin(2\theta_r) & \sin(2\theta_r) \\ \sin\left(2\theta_r + \frac{2\pi}{3}\right) & \sin(2\theta_r) & \sin\left(2\theta_r - \frac{2\pi}{3}\right) \end{bmatrix} \cdot \begin{bmatrix} i_a \\ i_b \\ i_c \end{bmatrix} - \frac{P}{2} \cdot \lambda_{pm} \cdot \begin{bmatrix} i_a \\ i_b \\ i_c \end{bmatrix} \cdot \begin{bmatrix} \sin(\theta_r) \\ \sin\left(\theta_r - \frac{2\pi}{3}\right) \\ \sin\left(\theta_r + \frac{2\pi}{3}\right) \end{bmatrix} \]

In the dq0 frame, the developed torque can be expressed as:

\[ T_{em} = \frac{3}{2} \cdot \frac{P}{2} \cdot \left(\lambda_{pm}i_q + (L_d - L_q)i_d\right) \]

The mechanical equations are:

\[ J \cdot \frac{d\omega_m}{dt} = T_{em} - B \cdot \omega_m - T_{load} \]
\[ \frac{d\theta}{dt} = \frac{P}{2} \cdot \omega_m \]

where \( B \) is a coefficient, \( T_{load} \) is the load torque, and \( P \) is the number of poles. The coefficient \( B \) is calculated from the moment of inertia \( J \) and the shaft time constant \( \tau_{shaft} \) as below:

\[ B = \frac{J}{\tau_{shaft}} \]

### 4.6.8 Permanent Magnet Synchronous Machine with Saturation

A 3-phase PMSM machine with saturation differs from that of a linear 3-phase PMSM machine in that the d-axis and q-axis magnetizing inductances \( L_{dm} \) and \( L_{qm} \) can be expressed as a nonlinear function of the d-axis and q-axis currents in the lookup table form.

The image and parameters of the machine are shown as follows.

**Image:**

![PM Motor Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_s ) (stator resistance)</td>
<td>Stator winding resistance, in Ohm</td>
</tr>
<tr>
<td>( L_s ) (stator leakage ind.)</td>
<td>Stator d-axis inductance, in H</td>
</tr>
<tr>
<td>Parameter</td>
<td>Description</td>
</tr>
<tr>
<td>-------------------------</td>
<td>---------------------------------------------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant, in V/krpm (mechanical speed). This value should be available from the machine data sheet. If not, it can be obtained through experiment by operating the machine as a generator at 1000 rpm and measuring the peak line-to-line voltage.</td>
</tr>
<tr>
<td>No. of Poles $P$</td>
<td>Number of poles $P$</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in kg·m²</td>
</tr>
<tr>
<td>Shaft Time Constant</td>
<td>Shaft time constant $\tau_{shaft}$, in sec. It is associated with the friction coefficient $B$ as: $B = J / \tau_{shaft}$.</td>
</tr>
<tr>
<td>$L_d$ Lookup Table File</td>
<td>File name of the lookup table for $L_{dm}$</td>
</tr>
<tr>
<td>$L_q$ Lookup Table File</td>
<td>File name of the lookup table for $L_{qm}$</td>
</tr>
<tr>
<td>dq Flag</td>
<td>Flag for the lookup table. When the flag is 0, $L_{dm}$ and $L_{qm}$ are function of $I_d$ and $I_q$. When the flag is 1, $L_{dm}$ and $L_{qm}$ are function of the current magnitude $I_m$ and the angle.</td>
</tr>
<tr>
<td>Transformation Flag</td>
<td>Flag for the transformation convention (see details below)</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal developed torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The relationship between the d-axis and q-axis inductances $L_d$ and $L_q$ and the magnetizing inductances $L_{dm}$ and $L_{qm}$ is as follows:

\[
L_d = L_s + L_{dm}
\]
\[
L_q = L_s + L_{qm}
\]

where $L_s$ is the stator leakage inductance. Since $L_s$ is normally very small, $L_d$ can be considered equivalent to $L_{dm}$, and $L_q$ can be considered equivalent to $L_{qm}$.

The Transformation Flag defines the transformation convention between the abc frame and the dq frame. When the Transformation Flag is 0:

\[
\begin{bmatrix}
I_d \\
I_q
\end{bmatrix} = \frac{2}{3} \begin{bmatrix}
\cos(\theta_r) & \cos(\theta_r - \frac{2\pi}{3}) & \cos(\theta_r + \frac{2\pi}{3}) \\
\sin(\theta_r) & -\sin(\theta_r - \frac{2\pi}{3}) & -\sin(\theta_r + \frac{2\pi}{3})
\end{bmatrix} \begin{bmatrix}
i_a \\
i_b \\
i_c
\end{bmatrix}
\]

\[
I_m = \sqrt{I_d^2 + I_q^2}
\]

\[
\theta_m = \text{atan2}(I_q, I_d)
\]

The current vector angle is in deg., and is from -180° to 180°.

When the Transformation Flag is 1:

\[
\begin{bmatrix}
I_d \\
I_q
\end{bmatrix} = \frac{\sqrt{2}}{\sqrt{3}} \begin{bmatrix}
\cos(\theta_r) & \cos(\theta_r - \frac{2\pi}{3}) & \cos(\theta_r + \frac{2\pi}{3}) \\
-\sin(\theta_r) & -\sin(\theta_r - \frac{2\pi}{3}) & -\sin(\theta_r + \frac{2\pi}{3})
\end{bmatrix} \begin{bmatrix}
i_a \\
i_b \\
i_c
\end{bmatrix}
\]
The current vector angle is in deg., and is from 0° to 360°.

The \( L_{dm} \) and \( L_{qm} \) lookup tables have the following format:

\[
\begin{align*}
M, N & \\
V_{r1}, V_{r2}, \ldots, V_{rM} & \\
V_{c1}, V_{c2}, \ldots, V_{cN} & \\
L_{11}, L_{12}, \ldots, L_{1N} & \\
L_{21}, L_{22}, \ldots, L_{2N} & \\
\vdots \ & \vdots \\
L_{M1}, L_{M2}, \ldots, L_{MN} & \\
\end{align*}
\]

where \( M \) is the number of rows and \( N \) is the number of columns; \( V_r \) is the row vector and \( V_c \) is the column vector; and \( L_{ij} \) is the \( L_{dm} \) or \( L_{qm} \) inductance value, in H, at Row \( i \) and Column \( j \). Note that Vectors \( V_r \) and \( V_c \) must be monotonically increasing.

When the \( dq \) flag is 0, the row vector is \( I_q \) and the column vector is \( I_d \). When the flag is 1, the row vector is the angle and the column vector is the amplitude \( I_m \).

If the input is between two points, interpolation is used to calculate the value. If the input is less than the minimum or greater than the maximum value, the input will be set to the minimum or maximum value.

This PMSM model with saturation can also be used as the linear PMSM model if the lookup tables are defined such that \( L_{dm} \) and \( L_{qm} \) are linear function of \( I_d \) and \( I_q \).

The following shows an example of the lookup table:

\[
\begin{align*}
4.15 & \\
-5.7155 & -4.8990 & -4.0825 & -3.2660 & \\
0.0109 & 0.0109 & 0.0107 & 0.0104 & 0.0102 & 0.0100 & 0.0098 & 0.0098 & 0.0098 & 0.0100 & 0.0102 & 0.0104 & 0.0107 & 0.0109 & 0.0096 & \\
0.0109 & 0.0109 & 0.0109 & 0.0106 & 0.0109 & 0.0106 & 0.0105 & 0.0105 & 0.0105 & 0.0106 & 0.0109 & 0.0109 & 0.0106 & 0.0109 & 0.0109 & 0.0096 & \\
0.0109 & 0.0109 & 0.0109 & 0.0109 & 0.0111 & 0.0108 & 0.0108 & 0.0108 & 0.0108 & 0.0111 & 0.0109 & 0.0109 & 0.0109 & 0.0109 & 0.0109 & 0.0096 & \\
0.0110 & 0.0110 & 0.0111 & 0.0110 & 0.0110 & 0.0109 & 0.0108 & 0.0107 & 0.0108 & 0.0109 & 0.0110 & 0.0110 & 0.0111 & 0.0111 & 0.0110 & 0.0110 & 0.0096 & \\
\end{align*}
\]
4.6.9 Switched Reluctance Machine

Three types of switched reluctance machine models are provided: 3-phase, 4-phase, and 5-phase.

Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Stator phase resistance $R$, in Ohm</td>
</tr>
<tr>
<td>Inductance $L_{min}$</td>
<td>Minimum phase inductance $L_{min}$, in H</td>
</tr>
<tr>
<td>Inductance $L_{max}$</td>
<td>Maximum phase inductance $L_{max}$, in H</td>
</tr>
<tr>
<td>Theta_min (deg.)</td>
<td>Duration of the interval $\theta_{min}$ where the inductance is at the minimum, in deg.</td>
</tr>
<tr>
<td>Theta_max (deg.)</td>
<td>Duration of the interval $\theta_{max}$ where the inductance is at the maximum, in deg.</td>
</tr>
<tr>
<td>Stator Pole Number</td>
<td>Number of stator poles (teeth)</td>
</tr>
<tr>
<td>Rotor Pole Number</td>
<td>Number of rotor poles (teeth)</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in kg*m$^2$</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

For more details on the definition and use of the master/slave flag, refer to Section 4.6.1.

The node assignments are: Nodes $a^+$, $a^-$, $b^+$, $b^-$, $c^+$, $c^-$, etc. are the stator winding terminals for Phase $a$, $b$, $c$, $d$, and $e$, respectively. The shaft node is the connecting terminal for the mechanical shaft. They are all power nodes and should be connected to the power circuit.

The equation of the switched reluctance machine for one phase is:

$$\dot{v} = i \cdot R + \frac{d(L \cdot i)}{dt}$$

where $v$ is the phase voltage, $i$ is the phase current, $R$ is the phase resistance, and $L$ is the phase inductance. The phase inductance $L$ is a function of the rotor angle $\theta$ (in electrical deg.), as shown in the following figure. The inductance profile is half-wave symmetrical. That is, it repeats itself after $180^\circ$. 
The rotor angle is defined such that, when the stator and the rotor teeth are completely aligned, \( \theta = 0 \). The value of the inductance can be in either rising stage, flat-top stage, falling stage, or flat-bottom stage.

If we define the constant \( k \) as the rising slope of the inductance from \( L_{\text{min}} \) to \( L_{\text{max}} \) (which is the same as the falling slope from \( L_{\text{max}} \) to \( L_{\text{min}} \)), and the interval of the rising/falling slope is \( \theta_{rf} \), we can express the inductance \( L \) as a function of the rotor angle \( \theta \) (from 0 to 180°) as follows:

\[
L = L_{\text{max}} \\
L = L_{\text{max}} - k \cdot \left( \theta - \frac{\theta_{\text{max}}}{2} \right) \\
L = L_{\text{min}} \\
L = L_{\text{min}} + k \cdot \left( \theta - \frac{\theta_{\text{max}}}{2} - \theta_{rf} - \theta_{\text{min}} \right) \\
L = L_{\text{max}} \quad \text{for} \quad \frac{\theta_{\text{max}}}{2} + 2\theta_{rf} + \theta_{\text{min}} + \theta \leq 180^\circ
\]

The developed torque of the machine per phase is:

\[
T_{em} = \frac{1}{2} \cdot i^2 \cdot \frac{dL}{d\theta}
\]

Based on the inductance expression, we have the developed torque in each stage as:

\[
T_{em} = \frac{i^2 k}{2} \quad \text{[rising stage]} \\
T_{em} = 0 \quad \text{[flat-top stage]} \\
T_{em} = -\frac{i^2 k}{2} \quad \text{[falling stage]} \\
T_{em} = 0 \quad \text{[flat-bottom stage]}
\]
4.6.10 Nonlinear Switched Reluctance Machine

In the previous switched reluctance models, the inductance is only a function of the rotor position, and it remains constant during the flat-top and flat-bottom states. In the nonlinear models, the inductance can be a nonlinear function of not only the rotor position, but also the current. The relationship between the inductance and the rotor position and current is defined through a 2-dimensional lookup table.

The images and parameters are shown as follows.

**Images:**

![3-phase Switched Reluctance Machine](image1)

![4-phase Switched Reluctance Machine](image2)

![5-phase Switched Reluctance Machine](image3)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance</td>
<td>Stator phase resistance $R$, in Ohm</td>
</tr>
<tr>
<td>Stator Pole Number</td>
<td>Number of stator poles (teeth)</td>
</tr>
<tr>
<td>Rotor Pole Number</td>
<td>Number of rotor poles (teeth)</td>
</tr>
<tr>
<td>Inductance Table File</td>
<td>File that stores the 2-dimensional table of the inductance versus the rotor position and current.</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia $J$ of the machine, in kg*m^2</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Output flag for internal torque $T_{em}$</td>
</tr>
<tr>
<td>Master/Slave Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

The inductance table file has the following format:

\[
m, n
\]

\[
\theta_1, \theta_2, \ldots, \theta_m
\]

\[
I_1, I_2, \ldots, I_n
\]

\[
L_{1,1}, L_{1,2}, \ldots, L_{1,n}
\]

\[
L_{2,1}, L_{2,2}, \ldots, L_{2,n}
\]

\[
\ldots \quad \ldots
\]

\[
L_{m,1}, L_{m,2}, \ldots, L_{m,n}
\]

where $m$ is the number of rows and $n$ is the number of columns; $\theta_1$ to $\theta_m$ is the row vector for the rotor position (in deg.), and $I_1$ and $I_n$ is the column vector for the phase current (in A); and $L_{i,j}$ is the inductance value (in H) at Row $i$ and Column $j$. For example, when the rotor position is $\theta_2$ and the phase current is $I_1$, the inductance is $L_{2,1}$.

Because of the half-wave symmetry, only inductance values from 0 to 180° need to be provided. Note that the row vector and column vector must be monotonically increasing.

The equation of a nonlinear switched reluctance machine for one phase is:
\[ v = i \cdot R + \frac{d(L \cdot i)}{dt} \]

where \( v \) is the phase voltage, \( i \) is the phase current, \( R \) is the phase resistance, and \( L \) is the phase inductance which depends on both the rotor angle and the current as defined by the lookup table.

The developed torque per phase is:

\[ T_{cm} = \frac{dW_{co}}{d\theta} \]

where \( W_{co} \) is the co-energy defined as:

\[ W_{co} = \int_{0}^{\theta} (L \cdot i) \cdot di \]

The integration and derivative calculations are done using the inductance lookup table.

### 4.6.11 Motor Control Blocks

The following control blocks for different machine types are provided:

- Maximum-Torque-Per-Ampere Control
- Field Weakening Control

#### 4.6.11.1 Maximum-Torque-Per-Ampere Control

There are two Maximum-Torque-Per-Ampere (MTPA) control blocks in PSIM’s Motor Drive Module. Their images are shown below. On the left side is the MTPA for linear internal permanent magnet synchronous machine (linear IPM), and on the right side is for nonlinear IPM.

**Images:**

**Attributes of MTPA for Linear IPM:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ld (d-axis inductance)</td>
<td>d-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Lq (q-axis inductance)</td>
<td>q-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant of the machine, in V/krpm (mechanical speed)</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Maximum Inverter Current</td>
<td>Maximum inverter output current amplitude (peak), in A</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>System base voltage value, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>System base current value, in A</td>
</tr>
<tr>
<td>Base Mechanical Speed</td>
<td>System base mechanical speed, in rad/sec</td>
</tr>
</tbody>
</table>

The Maximum-Torque-Per-Ampere control block has the following inputs and outputs, all in per-unit values:

- **Is:** Inverter current amplitude reference, input.
- **Id:** d-axis current reference, output.
Iq: q-axis current reference, output

This block is for the control of linear PMSM machines only. Given the current amplitude reference, this block will calculate the d-axis and q-axis current references \( I_d \) and \( I_q \) such that the maximum amount of torque is generated by the machine.

The block requires the parameters of the PMSM controlled and the inverter current rating.

**Attributes MPTA for Non-linear IPM:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Maximum Inverter Current</td>
<td>Maximum inverter output current amplitude (peak), in A</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>System base current value, in A</td>
</tr>
</tbody>
</table>

This block is for the control of nonlinear internal permanent magnet synchronous machines (IPM) only. It has the following inputs and outputs, all in per unit value except the inductances \( L_d \) and \( L_q \) and the flux linkage \( \Lambda \). If the base value \( I_b \) is set to 1, all input and output quantities are in real values.

**Input Signals:**
- \( I_s \): Inverter current amplitude reference
- \( L_d \): d-axis inductance \( L_d \), in H
- \( L_q \): q-axis inductance \( L_q \), in H
- \( \Lambda \): Peak stator phase flux linkage, in Weber

**Output Signals:**
- \( I_d \): d-axis current reference
- \( I_q \): q-axis current reference

Given the current amplitude reference, this block will calculate the d-axis and q-axis current references \( I_d \) and \( I_q \) such that the maximum amount of torque is generated by the machine.

### 4.6.11.2 Field Weakening Control

The images of field weakening control blocks are shown below.

**Images:**

- For IPM
- For IPM Non-linear
- For SPM
- For Induction Machine

**Attributes for Field Weakening (IPM):**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rs (stator resistance)</td>
<td>Stator winding resistance of the machine, in Ohm</td>
</tr>
<tr>
<td>Ld (d-axis inductance)</td>
<td>d-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Lq (q-axis inductance)</td>
<td>q-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant of the machine, in V/krpm (mechanical speed)</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
</tbody>
</table>
The field weakening (IPM) control block accepts the following input signals, all in per-unit value.

- **Is**: Inverter current amplitude reference
- **Vdc**: DC bus voltage feedback
- **Wm**: Motor mechanical speed, in rad/sec.

It has the following output signals, all in per-unit value:

- **Id**: d-axis current reference
- **Iq**: q-axis current reference

This block is for the control of linear PMSM machines only. When the machine speed is higher than a certain value, the machine will not be able to provide the maximum amount of torque. Instead, it will be limited by the machine power rating. Given the current amplitude reference, dc bus voltage, and the motor speed, the field weakening block will calculate the d-axis and q-axis current references \( Id \) and \( Iq \) to achieve a maximum power operation.

This block requires the parameters of the PMSM controlled and the inverter voltage and current ratings.

### Attributes for Field Weakening (Non-Linear IPM):

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Maximum Inverter Current</td>
<td>Maximum inverter output current amplitude (peak), in A</td>
</tr>
<tr>
<td>Maximum Inverter Voltage</td>
<td>Maximum inverter output voltage amplitude (phase peak), in V</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>System base voltage value, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>System base current value, in A</td>
</tr>
<tr>
<td>Base Mechanical Speed</td>
<td>System base mechanical speed, in rad/sec</td>
</tr>
</tbody>
</table>

The block has the following inputs and outputs, all in per unit value except \( Ld \), \( Lq \), and \( Lambda \). If base voltage value \( Vb \), \( Ib \), and \( Wmb \) are all set to 1, all input and output quantities are in true values.

**Input Signals:**

- **Is**: Inverter current amplitude reference.
- **Ld**: d-axis inductance at the rated operating conditions, in real value in H
- **Lq**: q-axis inductance at the rated operating conditions, in real value in H
- **Lambda**: Peak stator phase flux linkage at the rated operating conditions, in real value in Weber
- **Vdc**: DC bus voltage feedback
- **Wm**: Motor mechanical speed in rad/sec

**Output Signals:**

- **Id**: d-axis current reference.
- **Iq**: q-axis current reference.

This block is for the control of nonlinear interior PMSM (IPM) machines only. It is not for surface mounted PMSM (SPM) machines.

When the machine speed is higher than a certain value, the machine will not be able to generate the maximum...
torque. Instead, it will be limited by the machine power rating. Given the current amplitude reference, dc bus voltage, and the motor speed, the field weakening control block will calculate the d-axis and q-axis current references \( I_d \) and \( I_q \) to operate in the constant power region.

**Attributes for Field Weakening (SPM):**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( L_d ) (d-axis inductance)</td>
<td>The inductance on d-axis, in H</td>
</tr>
<tr>
<td>( V_{pk}/krpm )</td>
<td>The ratio of peak voltage versus speed, in V/krpm</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Maximum Inverter Current</td>
<td>Maximum inverter output current amplitude (peak), in A</td>
</tr>
<tr>
<td>Maximum Inverter Voltage</td>
<td>Maximum inverter output voltage amplitude (phase peak), in V</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>System base voltage value, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>System base current value, in A</td>
</tr>
<tr>
<td>Base Mechanical Speed</td>
<td>System base mechanical speed, in rad/sec</td>
</tr>
</tbody>
</table>

The block has the following inputs and outputs, all in per unit value. If base values \( V_b \), \( I_b \), and \( W_{mb} \) are all set at 1, input and output quantities are in real values.

Input Signals:
- \( I_s \): Inverter current amplitude reference
- \( V_{dc} \): DC bus voltage feedback
- \( W_m \): Motor mechanical speed

Output Signal:
- \( I_d \): d-axis current reference
- \( I_q \): q-axis current reference

This block is for the control of linear surface-mounted PMSM (SPM) machines only. It is not for internal PMSM (IPM) machines. In a SPM, the d-axis and q-axis inductance values are equal.

When the machine speed is higher than a certain value, the machine will not be able to generate the maximum torque. Instead, it will be limited by the machine power rating. Given the current amplitude, dc bus voltage, and the motor speed, the field weakening control block will calculate the d-axis and q-axis current references \( I_d \) and \( I_q \) to operate in the constant power region.

**Attributes for Field Weakening (IPM):**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>( R_s ) (stator)</td>
<td>Stator winding resistance of the machine, in Ohm</td>
</tr>
<tr>
<td>( L_{ls} ) (stator leakage)</td>
<td>Stator leakage inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>( R_r ) (rotor)</td>
<td>Rotor winding resistance of the machine, in Ohm</td>
</tr>
<tr>
<td>( L_{lr} ) (rotor leakage)</td>
<td>Rotor leakage inductance of the machine, in H</td>
</tr>
<tr>
<td>( L_m ) (magnetizing)</td>
<td>Magnetizing inductance, in H</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Rated Speed (rpm)</td>
<td>Rated speed of the machine, in rpm</td>
</tr>
<tr>
<td>AC Source Frequency</td>
<td>AC source frequency, in Hz</td>
</tr>
<tr>
<td>AC Voltage (line-line rms)</td>
<td>AC source voltage, line-to-line rms, in V</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>System base voltage value, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>System base current value, in A</td>
</tr>
</tbody>
</table>
The block has the following inputs and outputs, all in per unit value. If base values $V_b$, $I_b$, and $W_{mb}$ are all set at 1.0, all input and output quantities are in real values.

Input Signals:
- $V_{dc}$: DC bus voltage
- $W_e$: Stator electrical speed (in per unit, with the base value of $W_{mb}$)

Output Signal:
- $I_d$: d-axis current reference

This block is for the control of linear induction machines only.

When the machine speed is higher than a certain value, the machine will not be able to generate the maximum torque. Instead, it will be limited by the machine power rating. Given the dc bus voltage and the stator speed, the field weakening control block will calculate the d-axis current reference $I_d$ to operate in the constant power region.

### 4.7 MagCoupler Module

The MagCoupler Module provides interface for co-simulation between PSIM and the software JMAG. JMAG is an electromagnetic field analysis software for the development and design of electric machines, actuators, and other electrical and electronic devices and components. With the MagCoupler Module, one can perform power electronics and control in PSIM, and electromagnetic field analysis in JMAG.

The MagCoupler Module includes the MagCoupler-DL block and the MagCoupler block, as well as the mechanical elements and speed/torque/position sensors as described in Section 4.9.

The differences between the MagCoupler-DL block and the MagCoupler block and are:
- With the MagCoupler block, PSIM and JMAG run at the same time step, whereas with the MagCoupler-DL block, PSIM and JMAG can run at different time steps. The flexibility to set different time steps would make it possible to run JMAG at a larger time step and speed up the overall simulation.
- The interface ports of the MagCoupler block are signal ports. That is, electric currents do not flow into or out of the interface ports, and an electric current must first be converted into a voltage signal before it can be connected to the block. On the other hand, the MagCoupler-DL block is a native power element, and the interface ports behavior in the same way as other power circuit nodes (i.e. voltages can be applied and currents can flow in and out of the nodes). Because of the difference, the MagCoupler-DL block provides more efficient and robust interface between PSIM and JMAG.

To run the MagCoupler Module, the JMAG installation directory and the directories that include the JMAG DLL files "jbdll.dll" and "RT_Dll.dll" must be added to the PSIM’s search path. To add to PSIM’s search path, in PSIM, go to **Options >> Set Path**, and click on **Add Folder**.

Also, the MagCoupler Module requires Microsoft Internet Explorer Version 6 or higher. It will not work with Internet Explorer Version 5.

The description of the MagCoupler-DL block and the MagCoupler block is given below.
4.7.1 MagCoupler-DL Block

The MagCoupler-DL block has the following image and properties.

**Image:**

![MagCoupler-DL Block Image]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Netlist XML File</td>
<td>The file defines the interface between PSIM and JMAG. The file extension is .xml.</td>
</tr>
<tr>
<td>JMAG Input File</td>
<td>The JMAG input data file. It has the .jcf extension. Note that the .xml and .jcf files must be in the same directory.</td>
</tr>
<tr>
<td>JMAG Case Text</td>
<td>Comments for the JMAG circuit</td>
</tr>
<tr>
<td>Terminal Names</td>
<td>Terminal names of the block</td>
</tr>
</tbody>
</table>

The power circuit nodes and mechanical shaft nodes, as well as the rest of the interface between PSIM and the JMAG data files, are defined in the Netlist XML File. This file is in XML format, and is generated by JMAG. To specify this file, click on the browse button at the right of the edit field.

When a specific XML is selected, the .jcf data file will be read, and the terminals (nodes) of the block will be displayed. In the block image, the power circuit nodes will be placed at the top of the block, arranged from the left to the right. The mechanical shaft nodes will be placed on the left and right of the block, with the first shaft node on the right, and the second shaft node on the left.

The JMAG Input File is the JMAG data file for the device modeled. The file has the .jcf extension and is defined in the netlist XML file. Note that the .jcf file and the .xml file must be in the same directory.

The JMAG Case Text is a text identifying the specific JMAG study case. It can be any text.

The parameters of a sample permanent-magnet synchronous machine is shown below:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dt_of_JMAG</td>
<td>Time step used in JMAG.</td>
</tr>
<tr>
<td>Ir</td>
<td>Rated current. It is used in JMAG</td>
</tr>
<tr>
<td>dl_threshold</td>
<td>Current threshold. It is used in JMAG</td>
</tr>
<tr>
<td>dr_threshold</td>
<td>Displacement threshold. It is used in JMAG</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the machine, in kg*m^2.</td>
</tr>
<tr>
<td>Shaft Time Constant</td>
<td>Shaft time constant of the machine, in sec.</td>
</tr>
<tr>
<td>Back emf Flag</td>
<td>Display flag for all FEM coil currents (1: display; 0: no display)</td>
</tr>
<tr>
<td>Rotor Angle Flag</td>
<td>Display flag for all shaft angles</td>
</tr>
<tr>
<td>Speed Flag</td>
<td>Display flag for all shaft speeds</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Display flag for all developed torques</td>
</tr>
<tr>
<td>shaft1 Master Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>
Please consult JMAG manuals and documents on how to set up the co-simulation on the JMAG side.

4.7.2 MagCoupler Block

The MagCoupler block has the following image and properties.

**Image:**

![Block with 4 inputs and 4 outputs](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Link Table File</td>
<td>The XML file that defines the interface between PSIM and JMAG. It has the .xml extension.</td>
</tr>
<tr>
<td>JMAG Input File</td>
<td>The JCF input data file for JMAG. It has the .jcf extension. Note that the .xml file and the .jcf file must be in the same directory.</td>
</tr>
<tr>
<td>JMAG Case Text</td>
<td>Comments for the JMAG circuit</td>
</tr>
<tr>
<td>IN Nodes</td>
<td>Nodes that pass the values from PSIM to JMAG</td>
</tr>
<tr>
<td>OUT Nodes</td>
<td>Nodes that pass the values from JMAG to PSIM</td>
</tr>
</tbody>
</table>

The number of input and output nodes may vary, depending on the actual number of input/output nodes in a particular circuit.

The MagCoupler block accepts voltages, currents, and positions as inputs, and it provides voltages, currents, positions, torques, and force as the outputs. In PSIM, the MagCoupler block is a power circuit element. The way it interfaces with the rest of the circuit is that both the inputs and outputs are voltage signals (no electric current flows into the input node). To convert a branch current into a voltage signal, or vice versa, one can use a current-controlled voltage source, or voltage-controlled current source.

The **Link Table File**, in XML format, defines the input/output interface and corresponding functions in JMAG. This file is generated automatically by JMAG. To locate this file, click on the browse button at the right of the edit field.

The **JMAG Input File** is the JCF input data file that is read by the JMAG solver. The name is defined in the Link Table File.

Note that JCF input file .jcf must be in the same directory as the input link table file .xml. If any material database is used in JMAG, it should also be placed in the directory of the .xml file. Also, the .xml file does not have to be in the same directory as the schematic file. However, if a .xml file with the same name is present in the schematic directory, PSIM will read the one in the schematic directory first.

The **JMAG Case Text** is a text identifying the specific JMAG circuit. It can be any text describing the JMAG circuit.

The **IN Nodes** are the nodes through which PSIM passes the values to JMAG. In the MagCoupler block image, the order of the input nodes is from the top to the bottom. The order can be changed by highlighting the node and click on the upper or down arrow.

The **OUT Nodes** are the nodes through which JMAG passes the values back to PSIM. In the MagCoupler block image, the order of the output nodes is from the top to the bottom. The order can be changed by highlighting the node and click on the upper or down arrow.
By clicking on the **Edit Image** button, one can edit and customize the image of the MagCoupler block. Clicking on the **Display File** button will display the Link Table File in the Microsoft Internet Explorer environment, and clicking on the **Read File** button will read or re-load the Link Table File.

**Set-up in JMAG and PSIM:**

Using the MagCoupler block, it is easy to set up the link between JMAG and PSIM for co-simulation. It involves two main steps: setting up the circuit in JMAG and generating the link table file, and loading the link table file into PSIM.

An inductor example below is used to illustrate this process.

In the PSIM circuit of this example, the circuit on the left uses the built-in inductor element from the PSIM library, and the circuit on the right has the inductor implemented in JMAG. In this case, the inductor is modelled as a controlled current source in PSIM. The voltage across the inductor is first converted to a node-to-ground voltage through a voltage-controlled voltage source, and the value is passed to the input node VL of the MagCoupler block. At each time step, PSIM calls JMAG functions which calculate the inductor current based on the voltage input. This current is then sent back to PSIM in the voltage form, and is used to control the current source that represents the inductor.

In the JMAG circuit of this example, the voltage function (on the left side) receives the voltage from PSIM, and through the current probe in series with the FEM coil, the current is calculated and sent back to PSIM. The inductor structure in the JMAG environment is shown on the lower right.

The setup process of calling JMAG in PSIM through the MagCoupler block is as follows.

**In JMAG:**

- In the JMAG circuit, connect a voltage function to the right of the FEM coil. Under **Electrical Potential** in the property window, choose **Constant Value**, and set **Constant Value [V]** to 0.
- Connect a current probe to the left of the FEM coil.
- Connect another voltage function to the left of the current probe (the circuit will look like what is shown above). In the property window, choose **Cooperates with an external circuit simulator**.
- Highlight the inductor structure window. Go to the menu **Conditions >> Create Conditions**. From
the **Conditions List**, highlight **Coupled External Circuit Simulator**, and click **Modify**.

- On the **Coupled External Circuit Simulator** dialog window, there are two lists. The list on the right, called **JMAG**, contains all the functions that can be used to interface with PSIM. The list on the left, called **External Circuit Simulator**, contains the functions that are selected to interface with PSIM. In this case, there are two items in the JMAG list, one is the Voltage Function, and the other is the Current Probe.

- Highlight the Voltage Function, and click on the <- button to move the item from the list on the right to the list on the left. Repeat the same step to the Current Probe. Now both items should appear in the list on the left.

- Highlight the Voltage Function, and change the terminal name to VL. Also, change the Current Probe terminal name to iL. Close the dialog window.

- Go to the menu **File >> Export** and select **JCF...**. With the JCF file name defined as "inductor", the JCF file "inductor.jcf" and the link table file "inductor_csl.xml" will be generated.

- Copy the JCF file "inductor.jcf" and the link table file "inductor_csl.xml" to the folder containing the PSIM schematic file "inductor_jmag.sch". Rename the link table file to "inductor_jmag.xml". Note that the XML file does not have to be renamed, and both the JCF and XML files do not have to be moved to the folder of the schematic file. They are done here for the simplicity of file management.

**In PSIM:**

- After the rest of the power circuit is created, go to **Elements >> Power >> MagCoupler Module**, and select **MagCoupler Block**. Place the block on the schematic.

- Double click on the MagCoupler block to bring out the property window. Click on the browser button next to the **Link Table File** edit field to locate and select the file "inductor_jmag.xml". After the file is read, the property window will display the IN node VL and the OUT node iL.

- Connect the MagCoupler block to the rest of the circuit in the schematic.

The setup is now complete and the simulation is ready to run.

### 4.8 MagCoupler-RT Module

The MagCoupler-RT Module provides interface between PSIM and JMAG-RT data files. JMAG-RT is another way of modeling electromagnetic devices. The JMAG-RT data files are obtained by running the JMAG simulation in advance, and the data files are stored in a lookup table form. During the PSIM simulation, JMAG is not needed, and PSIM interfaces directly with the JMAG-RT data.

The biggest advantage of JMAG-RT is that, since the JMAG-RT data files are obtained from the JMAG dynamic simulation, the accuracy of the JMAG-RT model is comparable to that of a JMAG dynamic model. However, since JMAG is not involved in the PSIM simulation, the PSIM simulation is significantly faster.

The MagCoupler-RT Module includes the blocks described in this section, and mechanical elements and speed/torque/position sensors as described in Section 4.9.

Four MagCoupler-RT blocks are provided:

- 3-phase permanent-magnet synchronous machine (PMSM)
- 2-phase step machine
- Linear synchronous machine
- Linear solenoid

Each block has the dedicated image, as shown below.
Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Netlist XML File</td>
<td>The XML file that defines the interface between PSIM and JMAG-RT. It has the .xml extension.</td>
</tr>
<tr>
<td>JMAG-RT Input File</td>
<td>The JMAG-RT data file. It has the .rtt extension. Note that the .xml file and the .rtt file must be in the same directory.</td>
</tr>
<tr>
<td>JMAG Case Text</td>
<td>Comments for the JMAG-RT circuit</td>
</tr>
<tr>
<td>Terminal Names</td>
<td>Terminal names of the block</td>
</tr>
</tbody>
</table>

In the MagCoupler-RT block images, the power circuit nodes (such as $A$, $B$, $C$, $A^+$, $A^-$, $B^+$, $B^-$, $C^+$, $C^-$, $D^+$, and $D^-$ as shown above) are placed at the top of the block, arranged from the left to the right. The mechanical shaft nodes are placed on the left and right of the block, with the first shaft node (such as $M^+$ as shown above) on the right, and the second shaft node (such as $M^-$) on the left.

The electric nodes and rotor shaft nodes, as well as the rest of the interface between PSIM and the JMAG-RT data files (.rtt file), are defined in the Netlist XML File. This file is in XML format, and is generated by the JMAG-RT Manager. To specify this file, click on the browse button at the right of the edit field.

Note that for each type of MagCoupler-RT block, the "NetlistElement" must be the same as the predefined name. The predefined names are:
- "PM Synchronous Machine" for 3-phase PMSM
- "Step Machine" for 2-phase step machine
- "Linear Synchronous Machine" for linear synchronous machine
- "Linear Solenoid" for linear solenoid

For example, the first several lines of a netlist XML file for a PMSM may look like the following:

```xml
<?xml version="1.0" encoding="UTF-8"?>
<CircuitElement file="imp.rtt" name="MagCoupler-RT">
<NetlistElement type="JMAGRT" element="PM Synchronous Machine" pole_number="4">
... ...
```
The *JMAG-RT Input File* is the JMAG-RT data file for the device modeled. The file has the .rtt extension and is defined in the netlist XML file. Note that the .rtt file and the .xml file must be in the same directory.

The *JMAG Case Text* is a text identifying the specific JMAG-RT study case. It can be any text.

The *Terminal Names* are the names of the interface nodes.

The parameters of a 3-phase PMSM is shown below:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>shaft1_MomentofInertia</td>
<td>Moment of inertia of the machine, in kg*m²</td>
</tr>
<tr>
<td>shaft1_ShaftTimeConstant</td>
<td>Shaft time constant of the machine, in sec.</td>
</tr>
<tr>
<td>RU_resistance</td>
<td>Resistance of Phase U, in Ohm</td>
</tr>
<tr>
<td>RV_resistance</td>
<td>Resistance of Phase V, in Ohm</td>
</tr>
<tr>
<td>RW_resistance</td>
<td>Resistance of Phase W, in Ohm</td>
</tr>
<tr>
<td>OffsetAngle</td>
<td>Initial rotor angle, in mechanical deg.</td>
</tr>
<tr>
<td>coef_inductance</td>
<td>Inductance coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_flux</td>
<td>Flux coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_torque</td>
<td>Torque coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_magnet</td>
<td>Magnet coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_material</td>
<td>Material coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>turns_coil1</td>
<td>Coil 1 turns (used in JMAG-RT)</td>
</tr>
<tr>
<td>turns_coil2</td>
<td>Coil 2 turns (used in JMAG-RT)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag for 3-phase FEM coil currents (1: display; 0: no display)</td>
</tr>
<tr>
<td>Back emf Flag</td>
<td>Display flag for 3-phase FEM coil back emf</td>
</tr>
<tr>
<td>Rotor Angle Flag</td>
<td>Display flag for the rotor angle in mechanical deg.</td>
</tr>
<tr>
<td>Speed Flag</td>
<td>Display flag for the shaft mechanical speed in rad./sec.</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Display flag for the developed torque in N*m</td>
</tr>
<tr>
<td>shaft1 Master Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

The parameters of a 2-phase step machine is shown below:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>RA+</td>
<td>Resistance of Phase A+, in Ohm</td>
</tr>
<tr>
<td>RA-</td>
<td>Resistance of Phase A-, in Ohm</td>
</tr>
<tr>
<td>RB+</td>
<td>Resistance of Phase B+, in Ohm</td>
</tr>
<tr>
<td>RB-</td>
<td>Resistance of Phase B-, in Ohm</td>
</tr>
<tr>
<td>MomentofInertia</td>
<td>Moment of inertia of the machine, in kg*m²</td>
</tr>
<tr>
<td>ShaftTimeConstant</td>
<td>Shaft time constant of the machine, in sec.</td>
</tr>
<tr>
<td>OffsetAngle</td>
<td>Initial rotor angle, in mechanical deg.</td>
</tr>
<tr>
<td>turns_coil2</td>
<td>Coil 2 turns (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_inertial</td>
<td>Inertia 1 coefficient (used in JMAG-RT)</td>
</tr>
</tbody>
</table>
The parameters of a linear solenoid is shown below:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>coef_inertia2</td>
<td>Inertia 2 coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag for 3-phase FEM coil currents (1: display; 0: no display)</td>
</tr>
<tr>
<td>Back emf Flag</td>
<td>Display flag for 3-phase FEM coil back emf</td>
</tr>
<tr>
<td>Rotor Angle Flag</td>
<td>Display flag for the rotor angle in mechanical deg.</td>
</tr>
<tr>
<td>Speed Flag</td>
<td>Display flag for the shaft mechanical speed in rad./sec.</td>
</tr>
<tr>
<td>Torque Flag</td>
<td>Display flag for the developed torque in N*m</td>
</tr>
<tr>
<td>shaft1 Master Flag</td>
<td>Master/slave flag of the machine (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

The parameters of a linear synchronous machine is shown below:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>RU</td>
<td>Resistance of Phase U, in Ohm</td>
</tr>
<tr>
<td>RV</td>
<td>Resistance of Phase V, in Ohm</td>
</tr>
<tr>
<td>RW</td>
<td>Resistance of Phase W, in Ohm</td>
</tr>
<tr>
<td>Mass</td>
<td>Mass of the machine, in kg</td>
</tr>
<tr>
<td>ShaftTimeConstant</td>
<td>Shaft time constant of the solenoid, in sec.</td>
</tr>
<tr>
<td>OffsetDisp</td>
<td>Initial displacement, in m</td>
</tr>
<tr>
<td>turns_coil2</td>
<td>Coil 2 turns (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_mass1</td>
<td>Mass 1 coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_mass2</td>
<td>Mass 2 coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag for 3-phase FEM coil currents (1: display; 0: no display)</td>
</tr>
<tr>
<td>Back emf Flag</td>
<td>Display flag for 3-phase FEM coil back emf</td>
</tr>
<tr>
<td>Position Flag</td>
<td>Display flag for the solenoid position in m</td>
</tr>
<tr>
<td>Velocity Flag</td>
<td>Display flag for the solenoid velocity in m/sec.</td>
</tr>
<tr>
<td>Force Flag</td>
<td>Display flag for the developed force in N</td>
</tr>
<tr>
<td>mass1 Master Flag</td>
<td>Master/slave flag of the solenoid (1: master; 0: slave)</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>coef_inductance</td>
<td>Inductance coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_flux</td>
<td>Flux coefficient (used in JMAG-RT)</td>
</tr>
<tr>
<td>coef_force</td>
<td>Torque coefficient (used in JMAG-RT)</td>
</tr>
</tbody>
</table>
In all the parameter definitions above, except the flags (current flag, back emf flag, rotor angle/position flag, speed/velocity flag, torque/force flag, and master flag), all other parameters are read from the .rtt file defined in the XML file. These values can be changed, and for these parameters noted with "used in JMAG-RT", the changed values will be sent back to JMAG-RT for calculation.

Several MagCoupler-RT examples are provided under the "examples\MagCoupler-RT" folder.

### 4.9 Mechanical Elements and Sensors

This section describes elements that are shared by Motor Drive Module, MagCoupler Module, and MagCoupler-RT Module. The elements include mechanical loads, gear boxes, mechanical coupling blocks, mechanical-electrical interface blocks, and various speed/torque/position sensors.

#### 4.9.1 Mechanical Loads

Several mechanical load models are provided: constant-torque, constant-power, constant-speed, general-type, and externally controlled loads.

##### 4.9.1.1 Constant-Torque Load

The image of a constant-torque load is:

**Image:**

![Image of constant-torque load](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Constant Torque</td>
<td>Torque constant $T_{\text{const}}$, in N*m</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the load, in kg*m^2</td>
</tr>
</tbody>
</table>

If the reference direction of a mechanical system enters the dotted terminal, the load is along the reference direction, and the loading torque to the master machine is $T_{\text{const}}$. Otherwise the loading torque will be $-T_{\text{const}}$. See Section 2.6.1 for more detailed explanation on the reference direction.
A constant-torque load is expressed as:

\[ T_L = T_{\text{const}} \]

The torque does not depend on the speed direction.

### 4.9.1.2 Constant-Power Load

The image of a constant-power load is:

![Image](image1.png)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Maximum Torque</td>
<td>Maximum torque ( T_{\text{max}} ) of the load, in N*m</td>
</tr>
<tr>
<td>Base Speed</td>
<td>Base speed ( n_{\text{base}} ) of the load, in rpm</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the load, in kg*m^2</td>
</tr>
</tbody>
</table>

The torque-speed curve of a constant-power load is shown below:

![Image](image2.png)

When the mechanical speed is less than the base speed \( n_{\text{base}} \), the load torque is:

\[ T_L = T_{\text{max}} \]

When the mechanical speed is above the base speed, the load torque is:

\[ T_L = \frac{P}{\omega_m} \]

where \( P = T_{\text{max}} \cdot \omega_{\text{base}} \) and \( \omega_{\text{base}} = 2\pi n_{\text{base}}/60 \). The mechanical speed \( \omega_m \) is in rad./sec.

### 4.9.1.3 Constant-Speed Load

The image of a constant-speed load is:

![Image](image3.png)
A constant-speed mechanical load defines the speed of a mechanical system, and the speed will remain constant, as defined by the speed constant.

### 4.9.1.4 General-Type Load

The image of a general-type mechanical load is as follows.

**Image:**

![Image of general-type mechanical load]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Constant Speed (rpm)</td>
<td>Speed constant, in rpm</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the load, in kg*m²</td>
</tr>
</tbody>
</table>

A general-type load is expressed as:

\[ T_L = \text{sign}(\omega_m) \cdot \left( T_c + k_1 \cdot |\omega_m| + k_2 \cdot \omega_m^2 + k_3 \cdot |\omega_m|^3 \right) \]

where \( \omega_m \) is the mechanical speed in rad./sec.

Note that the torque of the general-type load is dependent on the speed direction.

### 4.9.1.5 Externally-Controlled Load

An externally-controlled mechanical load is used to define a load of an arbitrary load profile.

**Image:**

![Image of externally-controlled mechanical load]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Speed Flag</td>
<td>Flag for speed dependency</td>
</tr>
<tr>
<td></td>
<td>Flag = 0: The load is frictional and is always against the rotational direction; Flag = 1: The load is independent of the rotational direction.</td>
</tr>
<tr>
<td>Moment of Inertia</td>
<td>Moment of inertia of the load, in kg*m²</td>
</tr>
</tbody>
</table>
The value of the mechanical load is defined by the voltage value at the control node (1V corresponds to 1 N*m). This node is a control circuit node.

### 4.9.2 Gear Box

The image is a gear box shown below.

**Image:**

![Gear Box Diagram]

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gear Ratio</td>
<td>The gear ratio ( a )</td>
</tr>
<tr>
<td>Shaft 1 Master/Slave Flag</td>
<td>Master/slave flag for Shaft 1</td>
</tr>
<tr>
<td>Shaft 2 Master/Slave Flag</td>
<td>Master/slave flag for Shaft 2</td>
</tr>
</tbody>
</table>

The shaft with the bigger dot is Shaft 1.

If the numbers of teeth of the first gear and the second gear are \( n_1 \) and \( n_2 \), respectively, the gear ratio \( a \) is defined as: \( a = n_1 / n_2 \). Let the radius, torque, and speed of these two gears be: \( r_1, r_2, T_1, T_2, \omega_1, \) and \( \omega_2 \), we have: \( T_1 / T_2 = r_1 / r_2 = \omega_2 / \omega_1 = a \).

The two shafts of the gear box can be in either master mode or slave mode. For more information on the definition and use of the master/slave flag, refer to Section 4.6.1.

### 4.9.3 Mechanical Coupling Block

The mechanical coupler block is used to couple two mechanical systems.

**Image:**

![Mechanical Coupling Block Diagram]

This block is used in situations where both mechanical systems have a device in the master mode, and they must be connected together to form one system. Based on the connection convention in PSIM, a mechanical system can have only one master device. In this case, the mechanical coupling block can be inserted in between, and the mechanical system on each side of the coupling block can have its own device in the master mode.

### 4.9.4 Mechanical-Electrical Interface Block

This block allows users to access the internal equivalent circuit of the mechanical system of a machine.

**Image:**

![Mechanical-Electrical Interface Block Diagram]

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Master/Slave Flag</td>
<td>Flag for the master/slave mode (1: master, 0: slave)</td>
</tr>
</tbody>
</table>
Similar to electric machines, the mechanical-electrical interface block can be used to define the reference direction of a mechanical system through the master/slave flag. When the interface block is set to the master mode, the reference direction is along the mechanical shaft, away from the mechanical node, and towards the rest of the mechanical elements.

Let’s assume that a drive system consists of a motor (with a developed torque of $T_{em}$ and a moment of inertia of $J_1$) and a mechanical load (with a load torque of $T_{load}$ and a moment of inertia of $J_2$). The equation that describes the mechanical system is:

$$(J_1 + J_2) \frac{d\omega_m}{dt} = T_{em} - T_{load}$$

where $\omega_m$ is the shaft mechanical speed. In PSIM, this equation is modelled by an equivalent circuit as shown below.

In this circuit, the two current sources have the values of $T_{em}$ and $T_{load}$, and the capacitors have the values of $J_1$ and $J_2$. The node-to-ground voltage (speed node voltage) represents the mechanical speed $\omega_m$. This is analogous to $C \cdot \frac{dV}{dt} = i$ for a capacitor where $C = J_1 + J_2$, $V = \omega_m$, and $i = T_{em} - T_{load}$.

In PSIM, mechanical equivalent circuits for motors and mechanical loads all use the capacitor-based circuit model. The mechanical-electrical interface block provides the access to the internal mechanical equivalent circuit. If the mechanical side of an interface block (with the letters “M”) is connected to a mechanical shaft, the electrical side (with the letters “E”) will be the speed node of the mechanical equivalent circuit. One can thus connect any electrical circuits to this node.

With this element, users can connect built-in motors or mechanical loads with user-defined load or motor models.

**Example: An induction machine with a custom mechanical load model**

The figure below shows an induction machine connected to a user defined mechanical load model through the mechanical-electrical interface block. As explained above, the voltage at the electrical side represents the shaft mechanical speed. A current source flowing out of this node represents a mechanical load, and a capacitor connected to this node represents the load moment of inertia.

**Example: A custom machine model with a constant-torque load**

Similarly, one can build a custom machine model and connect it to the mechanical load in PSIM. The figure below shows such a circuit. The custom machine model must use the capacitor analogy to model the mechanical equation. The node representing the mechanical speed is then made available and is connected to the electrical side of the mechanical-electrical interface block.
4.9.5 Speed/Torque Sensors

A speed sensor or torque sensor is used to measure the mechanical speed or torque.

**Images:**

<table>
<thead>
<tr>
<th>Speed Sensor</th>
<th>Torque Sensor</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Speed Sensor Diagram" /></td>
<td><img src="image2.png" alt="Torque Sensor Diagram" /></td>
</tr>
</tbody>
</table>

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain of the sensor</td>
</tr>
</tbody>
</table>

The output of the speed sensor is in rpm.

The output of the speed/torque sensor depends on how the sensor is connected in a mechanical system.

For the speed sensor, if the sensor is along the reference direction of the mechanical system (refer to Section 2.8.1 for more details on the definition and use of the reference direction), a positive mechanical speed would give a positive sensor output. Otherwise, if the sensor is opposite to the reference direction of the mechanical system, a positive mechanical speed would give a negative sensor output.

For example, in the mechanical system below, Speed Sensor 1 is along the reference direction, and Speed Sensor 2 is opposite to the reference direction of the mechanical system. If the actual mechanical speed is positive, the output of Speed Sensor 1 will be positive, and the output of Speed Sensor 2 will be negative.

![Mechanical System Diagram](image3.png)

The torque sensor measures the torque difference between the dotted side of the sensor and the undotted side. To understand the physical meaning of the torque sensor measurement, we use the diagram below as an illustration.

The figure on the left shows a torque sensor connected with a 10-N*m mechanical load, and the reference direction of the mechanical system is from left to right. Based on the reference direction, if we use the right-hand method, by pointing the thumb in the reference direction and rotating the right hand, the direction of the fingers will show the direction of the positive speed and torque. The physical interpretation of the system is shown on the right.
In this case, the direction of the positive speed and torque is in the clockwise direction. The dotted side of the sensor is on the left, and the load is in such a way that it tries to slow down the shaft (the load torque is in the counter-clockwise direction).

The physical meaning of the torque sensor is that, if the dotted side of the sensor is fixed, the sensor will measure the torque tension on the undotted side of the sensor, and a positive sensor output would mean that the torque is opposite to the direction of the speed reference. Therefore, for the example above, the positive speed reference is in the clockwise direction, and the load torque is in the counter-clockwise direction. This will give a torque sensor reading of 10 N*m.

Similarly, if the undotted side of the sensor is fixed, the sensor will measure the torque tension on the dotted side of the sensor, in the positive direction of the speed reference. For example, in the system below, the torque sensor is flipped with the dotted side on the right. If the undotted side is fixed, the load torque is applied to the dotted side of the sensor, in the opposite direction of the speed reference. The torque sensor output will be -10 N*m instead.

To understand how the torque sensor is modeled in the equivalent circuit of the mechanical system, we use the following system as an example.

The system consists of one machine, 2 torque sensors, and 2 mechanical loads. The torques and moment of inertia for the machine and the loads are as labelled in the diagram. The reference direction of this mechanical system is from left to right. The equation for this system can be written as:

$$(J + J_{L1} + J_{L2}) \frac{d\omega_m}{dt} = T_{em} - T_{L1} - T_{L2}$$

The equivalent electrical circuit of the equation is shown below:
The node voltage in the circuit represents the mechanical speed $\omega_m$. The current probe on the left represents the reading of the Torque Sensor 1. Similarly, the current probe on the right represents the reading of the Torque Sensor 2. Note that the second current probe is from right to left since Sensor 2 is opposite to the reference direction of the mechanical system.

The equivalent circuit also illustrates how mechanical power is transferred. The multiplication of the current to the voltage, which is the same as the torque times the mechanical speed, represents the mechanical power. If the power is positive, it is transferred in the direction of the speed $\omega_m$.

### 4.9.6 Position Sensors

Four types of position sensors are provided: absolute encoder, incremental encoder, resolver, and hall effect position sensor. They are connected to the mechanical shaft, similar to the speed sensor and torque sensor, and the output signals are control signals.

#### 4.9.6.1 Absolute Encoder

An absolute encoder is a position sensor that provides the shaft position within a $360^\circ$ range (mechanical degree).

**Image:**

```
Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Position (deg.)</td>
<td>Initial shaft position, in deg.</td>
</tr>
<tr>
<td>No. of Bits of Resolution</td>
<td>Number of Bits of resolution N</td>
</tr>
</tbody>
</table>
```

The encoder output resolution is determined by the number of bits N. The encoder has two outputs: one is the number of counts (the range is from 0 to $2^N-1$), and the other is the position, in mechanical deg. (the range is from 0 to $360^\circ$).

An example of a PMSM drive system using the absolute encoder is given in the sample file "Absolute Encoder PMSM Drive.sch".

#### 4.9.6.2 Incremental Encoder

An incremental encoder is a position sensor that produces quadrature outputs which indicate the speed, angle, and direction of the shaft.

**Image:**
Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Position (deg.)</td>
<td>Initial shaft position, in deg.</td>
</tr>
<tr>
<td>No. of Lines</td>
<td>Number of lines that are in the code pattern of the code disk of the encoder</td>
</tr>
</tbody>
</table>

The two quadrature outputs are A and \( \overline{A} \) (\( \overline{A} \) is the inverse of A), and B and \( \overline{B} \). They are offset by 90°. In addition, the encoder provides separate index signal output Z and \( \overline{Z} \) that provide one count per revolution.

An example of an induction motor drive system using the incremental encoder is given in the sample file "Incremental Encoder INDM Drive.sch".

4.9.6.3 Resolver

A resolver is essentially a rotary transformer with one rotor winding and two stator windings. These two stator windings, referring to as the COS winding and SIN winding, are located 90° apart.

As the shaft rotates, the output voltages of the COS and SIN windings vary as the cosine and sine functions of the shaft angle.

Image:

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Position (deg.)</td>
<td>Initial shaft position, in deg.</td>
</tr>
<tr>
<td>No. of Poles</td>
<td>Number of poles of the resolver</td>
</tr>
</tbody>
</table>

The resolver has four outputs: \( \cos^+ \), \( \cos^- \) (the inverse of \( \cos^+ \)), \( \sin^+ \), and \( \sin^- \) (the inverse of \( \sin^+ \)). The peak amplitude of all the outputs is 1.

An example of a PMSM drive system using the resolver is given in the sample file "Resolver PMSM Drive.sch".

4.9.6.4 Hall Effect Sensor

A hall effect sensor is a type of position sensors that provides three pulses depending on the shaft position. The sensor consists of a set of semiconductor switches and trigger magnets. The switches open or close when the magnetic field is higher or lower than a certain threshold value.

Image:
Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Position (deg.)</td>
<td>Initial shaft position, in deg.</td>
</tr>
<tr>
<td>No. of Poles</td>
<td>Number of poles of the sensor</td>
</tr>
</tbody>
</table>

The hall effect sensor provides three logic signal outputs A, B, and C, which are spaced 120 electrical deg. apart.

The hall effect sensor is the same as the built-in hall effect sensor in the brushless dc machine.

Examples of BDCM motor drive systems using the hall effect sensor are given in the "examples" sub-folder of the PSIM directory.

4.10 Thermal Module

The Thermal Module is an add-on module to the PSIM program. It provides a quick way of estimating the losses of semiconductor devices (diodes, IGBT, and MOSFET), as well as the core and winding losses of inductors.

The core of the Thermal Module is the device database. A device database editor is provided to allow users to add new devices to the database and to manage the database easily. The devices in the database can then be used in the simulation for the loss calculation.

A database device simulation contains two parts of calculation:

- The behavior model of the device is used in the simulation. The behavior model of a switch takes into account the static characteristics (such as conduction voltage drop, on-state resistance, etc.), but not the dynamic characteristics (such as turn-on and turn-off transients). The behavior model of an inductor is an ideal inductor.
- Based on the voltage, current, and temperature values from the simulation, for switches, PSIM accesses the device database and calculates the conduction losses or switching losses. The static characteristics of the device are updated for the next simulation. For inductors, PSIM accesses the device database and calculates the core and winding losses.

Loss calculation of inductors takes into account the material characteristics of the device (such as core material, shape, winding type, size, and air gap, etc.).

Note that the loss calculation is only an approximation, and the accuracy of the results depends on the accuracy of the device data as well as the proper scaling of the results from the device test condition to the actual circuit operating conditions. Users should always verify the results with the measurement from experimental setup.

4.10.1 Diode Thermal Model

4.10.1.1 Diode Device in Database

The following information is defined for a diode device in the database:

**General Information:**

- Manufacturer: Device manufacture
- Part Number: Manufacturer’s part number
- Package: It can be discrete, dual, or 3-phase bridge package, as shown in the figure below:
In the images, beside the diode anode and cathode terminals, there are two extra nodes. The node with a dot is for the diode conduction losses $P_{\text{cond}}$ and the node without a dot is for the diode switching losses $P_{\text{sw}}$.

The style of the package (for example, TO-220, TO-247, etc.) can be specified in the Style field.

**Absolute Maximum Ratings:**
- $V_{\text{rrm, max}}$ (V): Peak reverse blocking voltage
- $I_{\text{F,max}}$ (A): Maximum dc current
- $T_{\text{j,max}}$ (°C): Maximum junction temperature

**Electrical Characteristics:**
- $V_d$ vs. $I_F$: Forward conduction voltage drop $V_d$ vs. forward current $I_F$
- $t_{rr}$ vs. $I_F$: Reverse recovery time $t_{rr}$ vs. current $I_F$
- $I_{rr}$ vs. $I_F$: Peak reverse recovery current $I_{rr}$ vs. current $I_F$
- $Q_{rr}$ vs. $I_F$: Reverse recovery charge $Q_{rr}$ vs. current $I_F$
- $E_{rr}$ vs. $I_F$: Reverse recovery energy losses $E_{rr}$ vs. current $I_F$

**Thermal Characteristics:**
- $R_{\text{th(j-c)}}$: Junction-to-case thermal resistance, in °C/W
- $R_{\text{th(c-s)}}$: Case-to-sink thermal resistance, in °C/W

**Dimensions and Weight:**
- Length (mm): Length of the device, in mm
- Height (mm): Height of the device, in mm
- Weight (g): Weight of the device, in g

Note that the condition "Reverse blocking voltage VR (V)" in characteristics $E_{rr}$ vs. $I_F$ is used to scale the loss calculation, and must be entered correctly.

Also, parameters under Absolute Maximum Ratings, Thermal Characteristics, and Dimensions and Weight are not used in the loss calculation, and are optional.

In addition, the diode forward conduction voltage drop $V_d$ changes depending on the forward current $I_F$. The new voltage drop is used in the subsequent simulation.

### 4.10.1.2 Diode Loss Calculation

A diode device in the database can be selected and used in the simulation for loss calculation. A diode in the Thermal Module library has the following parameters:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Device</td>
<td>The specific device selected from the device database</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz, under which the losses are calculated</td>
</tr>
</tbody>
</table>
The parameter \textit{Frequency} refers to the frequency under which the losses are calculated. For example, if the device operates at the switching frequency of 10 kHz, and the parameter \textit{Frequency} is also set to 10 kHz, the losses will be the values for one switching period. However, if the parameter \textit{Frequency} is set to 60 Hz, then the losses will be the value for a period of 60 Hz.

The parameter \textit{Pcond Calibration Factor} is the correction factor for the conduction losses. For the example, if the calculated conduction losses before the correction is \( P_{\text{cond\_cal}} \), then
\[
P_{\text{cond}} = K_{\text{cond}} \times P_{\text{cond\_cal}}
\]

Similarly, the parameter \textit{Psw Calibration Factor} is the correction factor for the switching losses. For the example, if the calculated switching losses before the correction is \( P_{\text{sw\_cal}} \), then
\[
P_{\text{sw}} = K_{\text{sw}} \times P_{\text{sw\_cal}}
\]

When several identical diodes are in parallel, one should have just one device in the schematic, and set the correct number of devices in the parameter input. This is because when several identical devices are in parallel in the schematic, the device currents may not be exactly equal due to small differences in the simulation. When the number of parallel devices is greater than one, the total current through the group of the parallel devices will be equally divided among the devices. The total losses are then obtained by multiplying the losses in each device by the number of parallel devices. The currents flowing out of Nodes \( P_{\text{cond}} \) and \( P_{\text{sw}} \) are the total losses of all the parallel devices combined.

The voltage at the conduction losses node \( P_{\text{cond}} \) or the switching losses node \( P_{\text{sw}} \) represents the calculated junction temperature \( T_j \) of the diode, and this junction temperature is used when the database curves are used for loss calculation. If the calculated \( T_j \) is between the junction temperatures of two curves, interpolation will be used. If the calculated \( T_j \) is lower than the lowest \( T_j \) or higher than the highest \( T_j \) in the curves, the curve corresponding to the lowest or highest \( T_j \) will be used. If there is only one curve, that curve is used regardless of the calculated \( T_j \).

\textbf{Conduction Losses:}

The diode conduction losses are calculated as:
\[
\text{Conduction Losses} = V_d \times I_F
\]
where \( V_d \) is the diode voltage drop, and \( I_F \) is the diode forward current. When the diode is conducting periodically with an on duty cycle of \( D \), the conduction losses are calculated as:
\[
\text{Conduction Losses} = V_d \times I_F \times D
\]

\textbf{Switching Losses:}

In calculating the switching losses, the diode turn-on losses are neglected and are not considered.

The diode turn-off losses due to the reverse recovery is calculated as:
\[
P_{\text{sw\_off}} = E_{rr} \times f \times V_R / V_{R\_datasheet}
\]
or
\[
P_{\text{sw\_off}} = 1/4 \times Q_{rr} \times V_R \times f
\]
where \( E_{rr} \) is the reverse recovery energy losses, \( Q_{rr} \) is the reverse recovery charge, \( f \) is the frequency as defined in the input parameter \textit{Frequency}, \( V_R \) is the actual reverse blocking voltage, and \( V_{R\_datasheet} \) is the reverse blocking voltage in the \( E_{rr} \) characteristics of the datasheet, defined as "Reverse blocking voltage VR (V)" in the test conditions.
If only one point is given for $Q_{rr}$, the loss calculation will be scaled based on the actual current $I_F$ as follows:

$$P_{sw\_off} = \frac{1}{4} * Q_{rr} * V_R * f * I_F / I_{F\_datasheet}$$

where $I_{F\_datasheet}$ is the test condition current under which $Q_{rr}$ and $t_{rr}$ are obtained.

The reverse recovery charge $Q_{rr}$ is defined as:

$$Q_{rr} = \frac{1}{2} * t_{rr} * I_{rr}$$

Whenever $E_{rr}$ is given in the device database, the losses will be calculated based on $E_{rr}$. If $E_{rr}$ is not given, the losses will be calculated based on $Q_{rr}$. If $Q_{rr}$ is not given, the losses will be calculated based on $t_{rr}$ and $I_{rr}$. If both are not given, the losses will be treated as 0.

The losses $P_{cond}$ and $P_{sw}$, in watts, are represented in the form of currents which flow out of these nodes. Therefore, to measure and display the losses, an ammeter should be connected between the $P_{cond}$ or $P_{sw}$ node and the ground. When they are not used, these two nodes cannot be floating, and must be connected to ground.

**Example: Diode Loss Calculation**

The circuit below shows a sample circuit that uses the Powerex’s discrete diode CS240650 (600V, 50A). The conduction losses and the switching losses are measured through two ammeters.

Once the information of the losses is available, by building the thermal equivalent circuit, the device junction temperature can be calculated. This junction temperature is in turn fed back and used in the loss calculation. The circuit shows a thermal circuit without considering the thermal transient.

4.10.2 IGBT Thermal Model

4.10.2.1 IGBT Device in Database

An IGBT device has three types of packages: discrete, dual, or 6-pack.

For the dual package, both the top and the bottom switches can be IGBT’s (full-bridge configuration), or one of the switches is IGBT and the other is a free-wheeling diode (half-bridge configuration). For the half-bridge dual IGBT device, since the free-wheeling diode parameters can be different from these of the anti-parallel diode, this type of device is referred to as the IGBT-Diode device, and is treated as a different type in the simulation. But for the convenience of discussion, both devices are referred to as the IGBT devices here.

The following information is defined for an IGBT device in the database:

**General Information:**
- Manufacturer: Device manufacture
- Part Number: Manufacturer’s part number
- Package: It can be discrete, dual, or 6-pack, as shown in the figure below
In the images, beside the IGBT and diode terminal nodes, there are four extra nodes from the top to the bottom (or from the left to the right on the top for the 6-pack package). They are the nodes for transistor conductor losses $P_{\text{cond}_Q}$ (the node with a circle), for transistor switching losses $P_{\text{sw}_Q}$, for diode conductor losses $P_{\text{cond}_D}$ (the node with a square), and for diode switching losses $P_{\text{sw}_D}$, respectively.

The style of the package (for example, TO-247, TO-268, etc.) can be specified in the Style field.

**Absolute Maximum Ratings:**
- $V_{\text{ce,max}}$ (V): Maximum collector-emitter voltage
- $I_{\text{c,max}}$ (A): Maximum collector current
- $T_{\text{j,max}}$ ($^\circ$C): Maximum junction temperature

**Electrical Characteristics - Transistor:**
- $V_{\text{ce(sat)}}$ vs. $I_{\text{c}}$: Collector-emitter saturation voltage $V_{\text{ce(sat)}}$ vs. collector current $I_{\text{c}}$
- $E_{\text{on}}$ vs. $I_{\text{c}}$: Turn-on energy losses $E_{\text{on}}$ vs. collector current $I_{\text{c}}$
- $E_{\text{off}}$ vs. $I_{\text{c}}$: Turn-off energy losses $E_{\text{off}}$ vs. collector current $I_{\text{c}}$

**Electrical Characteristics - Diode (or Anti-Parallel Diode):**
- $V_d$ vs. $I_F$: Forward conduction voltage drop $V_d$ vs. forward current $I_F$
- $t_{rr}$ vs. $I_F$: Reverse recovery time $t_{rr}$ vs. current $I_F$
- $I_{rr}$ vs. $I_F$: Peak reverse recovery current $I_{rr}$ vs. current $I_F$
- $Q_{rr}$ vs. $I_F$: Reverse recovery charge $Q_{rr}$ vs. current $I_F$
- $E_{rr}$ vs. $I_F$: Reverse recovery energy losses $E_{rr}$ vs. current $I_F$

**Electrical Characteristics - Free-Wheeling Diode (for IGBT-Diode device only):**
- $V_d$ vs. $I_F$: Forward conduction voltage drop vs. forward current $I_F$
- $t_{rr}$ vs. $I_F$: Reverse recovery time $t_{rr}$ vs. current $I_F$
- $I_{rr}$ vs. $I_F$: Peak reverse recovery current $I_{rr}$ vs. current $I_F$
- $Q_{rr}$ vs. $I_F$: Reverse recovery charge $Q_{rr}$ vs. current $I_F$
- $E_{rr}$ vs. $I_F$: Reverse recovery charge $E_{rr}$ vs. current $I_F$

**Thermal Characteristics:**
- $R_{\text{th(j-c)}}$ (transistor): Transistor junction-to-case thermal resistance, in $^\circ$C/W
- $R_{\text{th(j-c)}}$ (diode): Diode junction-to-case thermal resistance, in $^\circ$C/W
- $R_{\text{th(c-s)}}$: Case-to-sink thermal resistance, in $^\circ$C/W

**Dimensions and Weight:**
- Length (mm): Length of the device, in mm
- Width (mm): Width of the device, in mm
- Height (mm): Height of the device, in mm
- Weight (g): Weight of the device, in g
Note that the condition "DC bus voltage (V)" in the characteristics $E_{on}$ vs. $I_c$ and $E_{off}$ vs. $I_c$ for transistors, and the condition "Reverse blocking voltage VR (V)" in the characteristics $E_{rr}$ vs. $I_f$ for anti-parallel and free-wheeling diodes, are used to scale the loss calculation, and must be entered correctly.

Also, parameters under *Absolute Maximum Ratings*, *Thermal Characteristics*, and *Dimensions and Weight* are not used in the loss calculation, and are optional.

In addition, the collector-emitter saturation voltage $V_{ce(sat)}$ of the transistor and the forward conduction voltage drop $V_d$ of the diode change depending on the currents. The new values are used in the subsequent simulation.

### 4.10.2.2 IGBT Loss Calculation

An IGBT device in the database can be selected and used in the simulation for loss calculation. An IGBT device in the Thermal Module library has the following parameters:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Device</td>
<td>The specific device selected from the device database</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz, under which the losses are calculated</td>
</tr>
<tr>
<td>$P_{cond,Q}$ Calibration Factor</td>
<td>Calibration factor $K_{cond,Q}$ of the transistor conduction losses $P_{cond,Q}$</td>
</tr>
<tr>
<td>$P_{sw,Q}$ Calibration Factor</td>
<td>Calibration factor $K_{sw,Q}$ of the transistor switching losses $P_{sw,Q}$</td>
</tr>
<tr>
<td>$P_{cond,D}$ Calibration Factor</td>
<td>Calibration factor $K_{cond,D}$ of the diode conduction losses $P_{cond,D}$</td>
</tr>
<tr>
<td>$P_{sw,D}$ Calibration Factor</td>
<td>Calibration factor $K_{sw,D}$ of the diode switching losses $P_{sw,D}$</td>
</tr>
<tr>
<td>Number of Parallel Devices</td>
<td>Number of identical IGBT devices in parallel</td>
</tr>
</tbody>
</table>

The parameter *Frequency* refers to the frequency under which the losses are calculated. For example, if the device operates at the switching frequency of 10 kHz, and the parameter *Frequency* is also set to 10 kHz, the losses will be the values for one switching period. However, if the parameter *Frequency* is set to 60 Hz, then the losses will be the value for a period of 60 Hz.

The parameter $P_{cond,Q}$ *Calibration Factor* is the correction factor for the transistor conduction losses. For the example, if the calculated conduction losses before the correction is $P_{cond,Q,\ cal}$, then

$$P_{cond,Q} = K_{cond,Q} \times P_{cond,Q,\ cal}$$

Similarly, the parameter $P_{sw,Q}$ *Calibration Factor* is the correction factor for the transistor switching losses. For the example, if the calculated switching losses before the correction is $P_{sw,Q,\ cal}$, then

$$P_{sw,Q} = K_{sw,Q} \times P_{sw,Q,\ cal}$$

Parameters $P_{cond,D}$ *Calibration Factor* and $P_{sw,D}$ *Calibration Factor* work in the same way, except that they are for the diode losses.

When several identical IGBT devices are in parallel, one should have just one device in the schematic, and set the correct number of devices in the parameter input. This is because when several identical devices are in parallel in the schematic, the device currents may not be exactly equal due to small differences in the simulation. When the number of parallel devices is greater than one, the total current through the group of the parallel devices will be equally divided among the devices. The total losses are then obtained by multiplying the losses in each device by the number of parallel devices. The currents flowing out of Nodes $P_{cond,Q}$, $P_{sw,Q}$, $P_{cond,D}$, and $P_{sw,D}$ are the total losses of all the parallel devices combined.

The voltage at the conduction losses node $P_{cond,Q}$ or the switching losses node $P_{sw,Q}$ represents the calculated junction temperature $T_{j,Q}$ of the transistor, and the voltage at the conduction losses node $P_{cond,D}$ or the switching losses node $P_{sw,D}$ represents the calculated junction temperature $T_{j,D}$ of the anti-parallel diode, as
The calculated junction temperatures $T_{j,Q}$ and $T_{j,D}$ are used when the database curves are used for loss calculation. If the calculated junction temperature is between the junction temperatures of two curves, interpolation will be used. If the calculated junction temperature is lower than the lowest junction temperature or higher than the highest junction temperature in the curves, the curve corresponding to the lowest or highest junction temperature will be used. If there is only one curve, that curve is used regardless of the calculated junction temperature.

**Conduction Losses:**

The transistor conduction losses is calculated as:

$$P_{cond,Q} = V_{ce(sat)} \times I_c$$

where $V_{ce(sat)}$ is the transistor collector-emitter saturation voltage, and $I_c$ is the collector current. When the transistor is conducting periodically with an on duty cycle of $D$, the conduction losses are calculated as:

$$P_{cond,Q} = V_{ce(sat)} \times I_c \times D$$

**Switching Losses:**

The transistor turn-on losses is calculated as:

$$P_{sw,Q\_on} = E_{on} \times f \times V_{cc} / V_{cc\_datasheet}$$

where $E_{on}$ is the transistor turn-on energy losses, $f$ is the frequency as defined in the input parameter Frequency, $V_{cc}$ is the actual dc bus voltage, and $V_{cc\_datasheet}$ is the dc bus voltage in the $E_{on}$ and $E_{off}$ characteristics of the datasheet, defined as "DC bus voltage (V)" in the test conditions.

The transistor turn-off losses is calculated as:

$$P_{sw,Q\_off} = E_{off} \times f \times V_{cc} / V_{cc\_datasheet}$$

where $E_{off}$ is the transistor turn-off energy losses.

The loss calculation for the anti-parallel diode or free-wheeling diode is the same as described in the section for the diode device.

The losses $P_{cond,Q}$, $P_{sw,Q}$, $P_{cond,D}$, and $P_{sw,D}$, in watts, are represented in the form of currents which flow out of these nodes. Therefore, to measure and display the losses, an ammeter should be connected between the nodes and the ground. When they are not used, these nodes cannot be floating and must be connected to ground.

**Example: IGBT Loss Calculation**

The circuit below shows a sample circuit that uses Powerex’s 6-pack IGBT module CM100TU-12H (600V, 100A). The conduction losses and the switching losses of the transistors and the diodes are added separately, and a thermal equivalent circuit is provided to calculate the temperature raise.

With the Thermal Module, users can quickly check the thermal performance of a device under different operating conditions, and compare the devices of different manufactures.
4.10.3 IGBT-RB Thermal Model

4.10.3.1 IGBT-RB Device in Database

An IGBT-RB device has two types of packages: discrete or dual.

The following information is defined for an IGBT device in the database:

**General Information:**
- **Manufacturer:** Device manufacture
- **Part Number:** Manufacturer’s part number
- **Package:** It can be discrete or dual, as shown in the figure below

**Images:**

<table>
<thead>
<tr>
<th>Discrete</th>
<th>Dual</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Discrete IGBT-RB" /></td>
<td><img src="image2.png" alt="Dual IGBT-RB" /></td>
</tr>
</tbody>
</table>

In the images, beside the IGBT terminal nodes, there are two extra nodes. They are the nodes for transistor conductor losses $P_{cond_Q}$ (the node with a circle), and transistor switching losses $P_{sw_Q}$.

The style of the package can be specified in the **Style** field.

**Absolute Maximum Ratings:**
- $V_{ce,max}$ (V): Maximum collector-emitter voltage
- $I_{c,max}$ (A): Maximum collector current
- $T_{j,max}$ (°C): Maximum junction temperature

**Electrical Characteristics - Transistor:**
- $V_{ce(sat)}$ vs. $I_c$: Collector-emitter saturation voltage $V_{ce(sat)}$ vs. collector current $I_c$
\[ E_{on\ vs\ I_c}: \text{Turn-on energy losses } E_{on} \text{ vs. collector current } I_c \]
\[ E_{off\ vs\ I_c}: \text{Turn-off energy losses } E_{off} \text{ vs. collector current } I_c \]
\[ E_{rr\ vs\ I_c}: \text{Reverse recovery energy losses } E_{rr} \text{ vs. collector current } I_c \]

**Thermal Characteristics:**
- \( R_{th(j-c)} \) (transistor): Transistor junction-to-case thermal resistance, in \(^{\circ}\text{C/W}\)
- \( R_{th(c-s)} \): Case-to-sink thermal resistance, in \(^{\circ}\text{C/W}\)

**Dimensions and Weight:**
- Length (mm): Length of the device, in mm
- Width (mm): Width of the device, in mm
- Height (mm): Height of the device, in mm
- Weight (g): Weight of the device, in g

Note that the condition "DC bus voltage (V)" in the characteristics \( E_{on\ vs\ I_c} \) and \( E_{off\ vs\ I_c} \) for transistors, and the condition "Reverse blocking voltage VR (V)" in the characteristics \( E_{rr\ vs\ I_c} \) are used to scale the loss calculation, and must be entered correctly.

Also, parameters under *Absolute Maximum Ratings*, *Thermal Characteristics*, and *Dimensions and Weight* are not used in the loss calculation, and are optional.

In addition, the collector-emitter saturation voltage \( V_{ce(sat)} \) of the transistor depending on the currents. The new values are used in the subsequent simulation.

### 4.10.3.2 IGBT-RB Loss Calculation

An IGBT-RB device in the database can be selected and used in the simulation for loss calculation. An IGBT-RB device in the Thermal Module library has the following parameters:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Device</td>
<td>The specific device selected from the device database</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz, under which the losses are calculated</td>
</tr>
<tr>
<td>( P_{cond_Q\ Calibration\ Factor} )</td>
<td>Calibration factor ( K_{cond_Q} ) of the transistor conduction losses ( P_{cond_Q} )</td>
</tr>
<tr>
<td>( P_{sw_Q\ Calibration\ Factor} )</td>
<td>Calibration factor ( K_{sw_Q} ) of the transistor switching losses ( P_{sw_Q} )</td>
</tr>
<tr>
<td>Number of Parallel Devices</td>
<td>Number of identical IGBT-RB devices in parallel</td>
</tr>
</tbody>
</table>

The parameter *Frequency* refers to the frequency under which the losses are calculated. For example, if the device operates at the switching frequency of 10 kHz, and the parameter *Frequency* is also set to 10 kHz, the losses will be the values for one switching period. However, if the parameter *Frequency* is set to 60 Hz, then the losses will be the value for a period of 60 Hz.

The parameter *\( P_{cond\_Q\ Calibration\ Factor} \)* is the correction factor for the transistor conduction losses. For the example, if the calculated conduction losses before the correction is \( P_{cond\_Q\ cal} \), then
\[
P_{cond\_Q} = K_{cond\_Q} \times P_{cond\_Q\ cal}
\]

Similarly, the parameter *\( P_{sw\_Q\ Calibration\ Factor} \)* is the correction factor for the transistor switching losses. For the example, if the calculated switching losses before the correction is \( P_{sw\_Q\ cal} \), then
\[
P_{sw\_Q} = K_{sw\_Q} \times P_{sw\_Q\ cal}
\]

When several identical IGBT-RB devices are in parallel, one should have just one device in the schematic, and set the correct number of devices in the parameter input. This is because when several identical devices are in parallel in the schematic, the device currents may not be exactly equal due to small differences in the...
simulation. When the number of parallel devices is greater than one, the total current through the group of the parallel devices will be equally divided among the devices. The total losses are then obtained by multiplying the losses in each device by the number of parallel devices. The currents flowing out of Nodes $P_{\text{cond}_Q}$ and $P_{\text{sw}_Q}$ are the total losses of all the parallel devices combined.

The voltage at the conduction losses node $P_{\text{cond}_Q}$ or the switching losses node $P_{\text{sw}_Q}$ represents the calculated junction temperature $T_{j_Q}$ of the transistor.

The calculated junction temperature $T_{j_Q}$ is used when the database curves are used for loss calculation. If the calculated junction temperature is between the junction temperatures of two curves, interpolation will be used. If the calculated junction temperature is lower than the lowest junction temperature or higher than the highest junction temperature in the curves, the curve corresponding to the lowest or highest junction temperature will be used. If there is only one curve, that curve is used regardless of the calculated junction temperature.

**Conduction Losses:**

The transistor conduction losses is calculated as:

$$P_{\text{cond}_Q} = V_{\text{ce(sat)}} * I_c$$

where $V_{\text{ce(sat)}}$ is the transistor collector-emitter saturation voltage, and $I_c$ is the collector current. When the transistor is conducting periodically with an on duty cycle of $D$, the conduction losses are calculated as:

$$P_{\text{cond}_Q} = V_{\text{ce(sat)}} * I_c * D$$

**Switching Losses:**

The transistor turn-on losses is calculated as:

$$P_{\text{sw}_{\text{Q on}}} = E_{\text{on}} * f * V_{cc} / V_{cc_{\text{datasheet}}}$$

where $E_{\text{on}}$ is the device turn-on energy losses, $f$ is the frequency as defined in the input parameter Frequency, $V_{cc}$ is the actual dc bus voltage, and $V_{cc_{\text{datasheet}}}$ is the dc bus voltage in the $E_{\text{on}}$ and $E_{\text{off}}$ characteristics of the datasheet, defined as "DC bus voltage (V)" in the test conditions.

The transistor turn-off losses is calculated as:

$$P_{\text{sw}_{\text{Q off}}} = (E_{\text{off}} + E_{rr}) * f * V_{cc} / V_{cc_{\text{datasheet}}}$$

where $E_{\text{off}}$ is the transistor turn-off energy losses and $E_{rr}$ is the reverse recovery energy losses.

The losses $P_{\text{cond}_Q}$ and $P_{\text{sw}_Q}$, in watts, are represented in the form of currents which flow out of these nodes. Therefore, to measure and display the losses, an ammeter should be connected between the nodes and the ground. When they are not used, these nodes cannot be floating and must be connected to ground.

**4.10.4 MOSFET Thermal Model**

**4.10.4.1 MOSFET Device in Database**

The following information is defined for a MOSFET device in the database:

**General Information:**

- Manufacturer: Device manufacture
- Part Number: Manufacturer’s part number
- Package: Discrete, dual, or 6-pack, as shown in the figure below:
In the images, beside the MOSFET and diode terminal nodes, there are four extra nodes from the top to the bottom (or from the left to the right on the top for the 6-pack package). They are the node for transistor conductor losses \( P_{\text{cond}_Q} \) (the node with a circle), for transistor switching losses \( P_{\text{sw}_Q} \), for diode conductor losses \( P_{\text{cond}_D} \) (the node with a square), and for diode switching losses \( P_{\text{sw}_D} \), respectively.

The style of the package (for example, TO-220, TO-262, TO-247, etc.) can be specified in the Style field.

**Absolute Maximum Ratings:**
- \( V_{DS,\text{max}} \) (V): Maximum drain-to-source voltage
- \( I_{D,\text{max}} \) (A): Maximum continuous drain current
- \( T_{j,\text{max}} \) (°C): Maximum junction temperature

**Electrical Characteristics - Transistor:**
- \( R_{\text{DS(on)}} \) (ohm): Drain-to-source on-resistance \( R_{\text{DS(on)}} \) at the test conditions (test conditions: junction temperature \( T_{j,b} \) in °C (usually 25 °C), gate-to-source voltage \( V_{GS} \) in V, and drain current \( I_D \) in A)
- Temperature Coefficient: Temperature coefficient \( K_T \) of the on-resistance, in \( 1/\text{°C} \)
- \( V_{GS(th)} \) (V): Gate threshold voltage \( V_{GS(th)} \) (test condition: drain current \( I_D \) in A)
- \( g_{fs} \) (S): Forward transconductance \( g_{fs} \). In the linear region of the device, we have \( g_{fs} = \frac{I_D}{V_{GS}-V_{GS(th)}} \) (test conditions: drain-to-source voltage \( V_{DS} \) in V, and drain current \( I_D \) in A)
- \( t_r \) (ns) and \( t_f \) (ns): Rise time \( t_r \) and fall time \( t_f \) (test conditions: drain-to-source voltage \( V_{DS} \) in V; drain current \( I_D \) in A; and gate resistance \( R_g \) in ohm)
- \( Q_{gs}, Q_{gs'}, \) and \( Q_{gd} \): Total gate charge \( Q_{gs} \), gate-to-source charge \( Q_{gs'} \), and gate-to-drain ("Miller") charge \( Q_{gd} \), respectively, all in nC (test conditions: drain-to-source voltage \( V_{DS} \) in V; gate-to-source voltage \( V_{GS} \) in V, and drain current \( I_D \) in A)
- \( C_{iss}, C_{oss}, \) and \( C_{rss} \): Input capacitance \( C_{iss} \), output capacitance \( C_{oss} \), and reverse transfer capacitance \( C_{rss} \), respectively, all in pF (test conditions: drain-to-source voltage \( V_{DS} \) in V; gate-to-source voltage \( V_{DS} \) in V; and test frequency in MHz)

**Electrical Characteristics - Diode:**
- \( V_d \) vs. \( I_F \): Forward conduction voltage drop \( V_d \) vs. forward current \( I_F \)
- \( t_r \) and \( Q_{rr} \): Reverse recovery time \( t_r \) in ns, and reverse recovery charge \( Q_{rr} \) in uC (test conditions: forward current \( I_F \) in A; rate of change of the current di/dt in A/us, and junction temperature \( T_j \) in °C)

**Thermal Characteristics:**
- \( R_{\text{th(j-c)}} \): Junction-to-case thermal resistance, in °C/W
- \( R_{\text{th(c-s)}} \): Case-to-sink thermal resistance, in °C/W
Dimensions and Weight:

- Length (mm): Length of the device, in mm
- Width (mm): Width of the device, in mm
- Height (mm): Height of the device, in mm
- Weight (g): Weight of the device, in g

Note that the parameters under Absolute Maximum Ratings, Thermal Characteristics, and Dimensions and Weight, and the rise time \( t_r \) and fall time \( t_f \) parameters, are not used in the loss calculation, and are optional.

The MOSFET on-resistance is a function of the transistor junction temperature. The voltage at the node \( P_{cond, Q} \) or \( P_{sw, Q} \) of the MOSFET image represents the calculated transistor junction temperature \( T_j \) in °C. For example, a voltage value of 25V would mean a junction temperature of 25°C. The on-resistance of the MOSFET is expressed as:

\[
R_{(DS)on} = R_{(DS)on, b} \cdot (1 + K_T \cdot (T_j - T_{j, b}))
\]

The temperature coefficient is calculated as:

\[
K_T = \frac{R_{(DS)on} - 1}{T_j - T_{j, b}}
\]

The base values are normally obtained at the test conditions of 25°C. Using the normalized value of \( R_{DS(on)} \) based on the base value, we have:

\[
K_T = \frac{R_{(DS)on \ normalized} - 1}{T_j - 25}
\]

The on-resistance \( R_{DS(on)} \) is calculated at every time step and is used in the simulation.

Also, the forward conduction voltage drop \( V_d \) of the diode changes depending on the current. The new conduction voltage value is used in the simulation.

### 4.10.4.2 MOSFET Loss Calculation

A MOSFET device in the database can be selected and used in the simulation for loss calculation. A MOSFET in the Thermal Module library has the following parameters:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Device</td>
<td>The specific device selected from the device database</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz, under which the losses are calculated</td>
</tr>
<tr>
<td>( V_{GG+} ) (upper level)</td>
<td>Upper level of the gate source voltage, in V</td>
</tr>
<tr>
<td>( V_{GG-} ) (lower level)</td>
<td>Lower level of the gate source voltage, in V</td>
</tr>
<tr>
<td>( R_{g, on} ) (turn-on)</td>
<td>Gate resistance during turn-on</td>
</tr>
<tr>
<td>( R_{g, off} ) (turn-off)</td>
<td>Gate resistance during turn-off. In most cases, the turn-on gate resistance ( R_{g, on} ) and the turn-off gate resistance ( R_{g, off} ) are identical.</td>
</tr>
<tr>
<td>( R_{DS(on)} ) Calibration Factor</td>
<td>The calibration factor of the on-state resistance ( R_{DS(on)} )</td>
</tr>
<tr>
<td>( g_{fs} ) Calibration Factor</td>
<td>The calibration factor of the forward transconductance ( g_{fs} )</td>
</tr>
<tr>
<td>( P_{cond, Q} ) Calibration Factor</td>
<td>The calibration factor ( K_{cond, Q} ) of the transistor conduction losses ( P_{cond, Q} )</td>
</tr>
<tr>
<td>( P_{sw, Q} ) Calibration Factor</td>
<td>The calibration factor ( K_{sw, Q} ) of the transistor switching losses ( P_{sw, Q} )</td>
</tr>
</tbody>
</table>
The parameter *Frequency* refers to the frequency under which the losses are calculated. For example, if the device operates at the switching frequency of 10 kHz, and the parameter *Frequency* is also set to 10 kHz, the losses will be the values for one switching period. However, if the parameter *Frequency* is set to 60 Hz, then the losses will be the value for a period of 60 Hz.

The parameter $P_{\text{cond}, Q}$ *Calibration Factor* is the correction factor for the transistor conduction losses. For the example, if the calculated conduction losses before the correction is $P_{\text{cond}, Q, \text{cal}}$, then

$$P_{\text{cond}, Q} = K_{\text{cond}, Q} \cdot P_{\text{cond}, Q, \text{cal}}$$

Similarly, the parameter $P_{\text{sw}, Q}$ *Calibration Factor* is the correction factor for the transistor switching losses. For the example, if the calculated switching losses before the correction is $P_{\text{sw}, Q, \text{cal}}$, then

$$P_{\text{sw}, Q} = K_{\text{sw}, Q} \cdot P_{\text{sw}, Q, \text{cal}}$$

Parameters $P_{\text{cond}, D}$ *Calibration Factor* and $P_{\text{sw}, D}$ *Calibration Factor* work in the same way, except that they are for the diode losses.

When several identical MOSFET devices are in parallel, one should have just one device in the schematic, and set the correct number of devices in the parameter input. This is because when several identical devices are in parallel in the schematic, the device currents may not be exactly equal due to small differences in the simulation. When the number of parallel devices is greater than one, the total current through the group of the parallel devices will be equally divided among the devices. The total losses are then obtained by multiplying the losses in each device by the number of parallel devices. The currents flowing out of Nodes $P_{\text{cond}, D}$, $P_{\text{sw}, D}$, $P_{\text{cond}, Q}$, and $P_{\text{sw}, Q}$ are the total losses of all the parallel devices combined.

The voltage at the diode loss node $P_{\text{cond}, D}$ or $P_{\text{sw}, D}$ of the MOSFET image represents the calculated junction temperature $T_J$ of the anti-parallel diode, and this junction temperature is used when the database curves are used for determining the forward conduction diode voltage drop. If the calculated $T_J$ is between the junction temperatures of two curves, interpolation will be used. If the calculated $T_J$ is lower than the lowest $T_J$ or higher than the highest $T_J$ in the curves, the curve corresponding to the lowest or highest $T_J$ will be used. If there is only one curve, that curve is used regardless of the calculated $T_J$.

**Conduction Losses:**

The transistor conduction losses is calculated as:

$$P_{\text{cond}, Q} = I_D^2 \cdot R_{\text{DS(on)}}$$

where $I_D$ is the drain current, and $R_{\text{DS(on)}}$ is the static on-resistance. When the transistor is conducting periodically with an on duty cycle of $D$, the conduction losses are calculated as:

$$P_{\text{cond}, Q} = I_D^2 \cdot R_{\text{DS(on)}} \cdot D$$

**Switching Losses:**

The transistor turn-on losses is calculated as:

$$P_{\text{sw}, Q, \text{on}} = E_{\text{on}} \cdot f$$

where $E_{\text{on}}$ is the transistor turn-on energy losses, and $f$ is the frequency as defined in the input parameter *Frequency*.

The transistor turn-off losses is calculated as:

$$P_{\text{sw}, Q, \text{off}} = E_{\text{off}} \cdot f$$

where $E_{\text{off}}$ is the transistor turn-off energy losses.

The energy losses $E_{\text{on}}$ and $E_{\text{off}}$ are calculated using the rise times and the fall times of the voltage and current.
waveforms based on the information of the MOSFET gate current, input/output/reverse transfer capacitances, and gate charges.

Please note that the gate charge losses are not included in the switching losses above. The gate charge losses are usually quite small compared to the turn-on/turn-off switching losses, and can be neglected in the full load conditions. However, they can become substantial in the light load conditions. To calculate the gate charge losses $P_{loss_{Qg}}$:

$$P_{loss_{Qg}} = Q_g \times V_{GG} \times f_{sw}$$

where $Q_g$ is the total gate charge, $V_{GG}$ is the gate source voltage, and $f_{sw}$ is the switching frequency.

Also, the MOSFET device must be properly selected to ensure that it is sufficiently rated to conduct the current. If the MOSFET current rating is too low, PSIM will not be able to calculate the switching rise/fall times and will give an error message. In simulation, the maximum drain-to-source current that a MOSFET device is allowed to conduct is:

$$I_{o,\text{max}} = g_{fs} \times (V_{GG} - V_{GS(th)})$$

If the current exceeds $I_{o,\text{max}}$, one should either increase the gate source voltage level or select another MOSFET device with a larger forward transconductance value.

The loss calculation for the anti-parallel diode or free-wheeling diode is the same as described in the diode device section.

The losses $P_{cond_{Q}}, P_{sw_{Q}}, P_{cond_{D}},$ and $P_{sw_{D}}$, in watts, are represented in the form of currents which flow out of these nodes. Therefore, to measure and display the losses, an ammeter should be connected between the nodes and the ground. When they are not used, these nodes cannot be floating and must be connected to ground.

4.10.5 Inductor Thermal Model

4.10.5.1 Inductor in Database

The following information is defined for an inductor in the database:

**General Information:**
- Manufacturer: Inductor manufacture
- Part Number: Inductor manufacturer’s part number
- Package: Only the basic package is available.

**Image:**

![Inductor Diagram]

**Electrical Characteristics:**
- $L$ (uH): Inductance, in uH

**Maximum Ratings:**
- $I_{max,rms}$ (A): Maximum rms current rating, in A.

**Core Information:**
- Core Type and Size: Specify core shape and size
- Core Material: Specify core material and magnetic characteristics

**Winding Information:**
- Winding Type and Size: Specify conductor shape, size, and insulation type
- Winding Distribution: Specify winding number of turns, layers, distance between layers, distance between wires, and distance between core and winding
- Distribution of Parallel Wires: Specify parallel wire distribution in radial and height directions
4.10.5.2 Inductor Loss Calculation

A database inductor can be selected and used in the simulation for loss calculation. An inductor in the Thermal Module library has the following parameters:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Device</td>
<td>The specific inductor selected from the device database.</td>
</tr>
<tr>
<td>Frequency</td>
<td>Fundamental frequency of the inductor, in Hz.</td>
</tr>
<tr>
<td>Temperature Flag</td>
<td>The flag that defines how core temperature is defined. It can be either <em>Calculated</em> or <em>Fixed</em>. If it is <em>Calculated</em>, the core temperature will be calculated based on circuit operating conditions and this temperature will be used for loss calculation. If it is <em>Fixed</em>, the core temperature will be specified by users. This will give users a clear idea the losses at a specific temperature.</td>
</tr>
<tr>
<td>Ambient Temperature</td>
<td>The ambient temperature of the inductor, in °C.</td>
</tr>
<tr>
<td>Convection</td>
<td>Type of cooling. It can be <em>Forced</em> for forced convection or <em>Natural</em> for natural convection.</td>
</tr>
<tr>
<td>Air Speed</td>
<td>The air speed, in m/sec., if forced convection is selected.</td>
</tr>
<tr>
<td>Estimated Core Temp.</td>
<td>Estimated core temperature, in °C, if the Temperature Flag is set to Fixed.</td>
</tr>
<tr>
<td>Estimated Winding Temp.</td>
<td>Estimated winding temperature, in °C, if the Temperature Flag is set to Fixed.</td>
</tr>
<tr>
<td>Loss Calculation Flag</td>
<td>If the flag is 0, the loss calculation will be performed from the beginning of the simulation. If the flag is 1, the loss calculation will be performed only in the last fundamental cycle of the simulation. Since loss calculation will slow down simulation, calculating the losses only in the last cycle will speed up the simulation.</td>
</tr>
<tr>
<td>Current Flag</td>
<td>Display flag of the inductor current.</td>
</tr>
</tbody>
</table>

The losses $P_{\text{core}}$ and $P_{\text{winding}}$, in watts, are represented in the form of currents which flow out of the nodes. To measure and display the losses, an ammeter should be connected between the nodes and the ground. When they are not used, these nodes cannot be floating and must be connected to ground.

In the parameters, **Frequency** refers to the main frequency under which the inductor is excited. For example, if an inductor conducts a 60-Hz current in an ac circuit which also has 20kHz switching harmonic components, the frequency should be set to 60 Hz. If an inductor conducts dc current in a dc circuit which has 20kHz switching harmonic components, the frequency should be set to 20kHz.

For more information on how to use the Thermal Module inductor, please refer to the tutorial "Tutorial - Inductor loss calculation in Thermal Module.pdf".
4.10.6 Device Database Editor

The device database editor, PcdEditor.exe, provides an easy and convenient way of adding, editing, and managing devices.

Pull down PSIM’s Utilities menu, an image of the database editor is shown below.

On the left are the device database files that are loaded into the database editor, and the list of the devices. The devices can be displayed based on either Device Type or Manufacturer. Also, the device list can be sorted by Part Number, Voltage rating, or Current rating, by clicking on the title bars of the list.

To create a new device file, choose File >> New Device File.

To load a device files into the editor, choose File >> Open Device File.

To unload a device file from the editor, choose File >> Close Device File.

On the right is the information of each device. In general, the following information is required to define a switching device for thermal simulation:
- Manufacturer and Part Number
- Package type and style
- Absolute maximum ratings
- Electrical characteristics
- Thermal characteristics
- Dimension and weight

The following information are required to define a database inductor for thermal simulation.
- Manufacturer and Part Number
- Package type and style
- Maximum ratings
- Electrical characteristics
- Core, winding, and gap information

Five types of elements can be added to a database device file: inductor and four types of switching devices: diode, IGBT, dual IGBT-diode modules, and MOSFET.
To create a new device, go to the **Device** menu, and choose either **New Diode**, **New IGBT**, **New IGBT-Diode**, **New MOSFET**, or **New Inductor**.

To make a copy of an existing device in the same database file, highlight the device in the list, and choose **Device >> Save Device As**.

To make a copy of an existing device and save it in a different database file, first highlight the device in the list, then highlight the file name in the File Name list, and choose **Device >> Save Device As**.

### 4.10.7 Adding a Switching Device to Database

The step-by-step procedure is illustrated with an example: add Powerex discrete diode CS240650 (600V, 50A) into a new device database file "diode_new.dev".

- **Create new device file**: Launch PcdEditor.exe. Go to **File >> New Device File**, and create a file called "diode_new.dev". This file will be placed in the *device* sub-folder under the PSIM program folder by default.

- **Create new device**: With the file name "diode_new" highlighted in the "File Name" list, Choose **Device >> New Diode**. A diode will be added to the database file with *Manufacturer* as "New" and *Part Number* as "New".

- **Enter basic information**: Obtain the datasheet of Powerex diode CS240650 from the web site www.pwrx.com. By referring to the information from the datasheet, in the database editor, enter the following information for this device:
  - Manufacturer: Powerex
  - Part Number: CS240650
  - Package: Discrete

  and under *Absolute Maximum Ratings*:
  - \( V_{rrm, \text{max}} \) (V): 600
  - \( I_{F, \text{max}} \) (A): 50
  - \( T_{j, \text{max}} \) (°C): 150

- **Define forward voltage characteristics \( V_d \) vs. \( I_F \)**:

  Under *Electrical Characteristics* by clicking on the **Edit** button on top of the \( V_d \) vs. \( I_F \) graph area. The following dialog window will appear.
The dialog window has two pages: *Graph* and *Conditions*.

The *Graph* page contains the x and y axis settings as well as the data points and the graph. In this case, the y axis is the conduction voltage drop $V_d$, and the x axis is the forward current $I_F$. The x and y axis can have multiplying factors (such as $m$ for $10^{-3}$, $u$ for $10^{-6}$, etc.).

The *Conditions* page contains the conditions under which the graph is obtained.

There are two ways to define the graph:

- Enter the graph data points manually if there are only a few data points
- Use the Graph Wizard to capture the graph directly from the datasheet image if the graph image is available from datasheet.

**To Define the Graph Manually:**

- On the datasheet, refer to the "Maximum On-State Characteristics", and enter the values for the x/y axis settings as follows:
  - $X_0$: 1
  - $X_{max}$: 1000
  - $Y_0$: 0.6
  - $Y_{max}$: 2.6
  - X in log: checked
- Visually inspect the graph, and select a few data points. Enter the data points in the data area as follows, then click on the **Refresh** button to display the graph:
  - (1,0.7) (10,1.05) (100,1.8) (200,2.2) (300,2.4)

Or if the data is in an Excel file, it can be copied directly from Excel into the data area. The figure on the left shows the data in Excel. To copy the data, select the two data columns as shown in the figure on the right, press Ctrl-C to copy. Then move the cursor into the data area, and press Ctrl-V to paste.
• Click on the **Conditions** tab and enter the **Junction Temperature** as 25 °C.

Alternatively, the graph can be defined in this case using the Graph Wizard.

**To Define the Graph Using the Graph Wizard:**

• Click on the **Add Curve** button. Then click on the forward wizard icon to start the Graph Wizard.

• Display the graph of the datasheet on the screen as follows, then press the Print Screen key (the key is labeled as "Prnt Scrl" on some keyboards) to copy the screen image to the clipboard.

• Click on the forward wizard icon to paste the screen image into the graph window in the database editor. Position the graph image properly in the graph window by dragging the left mouse so that the complete graph is displayed within the window.

• If the graph image is either too large or too small, go back to the previous step by clicking on the backward wizard icon. Then resize the image of the graph in the Adobe Acrobat, and copy the screen image to the clipboard again.

• The graph dialog window should look something like follows. Click on the forward wizard icon to move on to the next step.
• In this step, the border of the graph area is defined by first left clicking at the origin of the graph (usually the lower left corner), then left clicking again at the opposite corner of the origin (usually the upper right corner). Note that the graph origin does not have to be the lower left corner, and it can be any one of the four corners.

• To locate the origin of the corner more accurately, right mouse click to zoom in, and press the Esc (escape) key to exit the zoom. After this, a blue rectangle will appear around the border of the graph, and the dialog window will appear as follows.

Then click on the forward wizard icon to move on to the next step.

• In this step, the x and y axis settings will be defined. Enter the settings as follows:
X0: 1
Xmax: 1000
Y0: 0.6
Ymax: 2.6

• Leave the checkbox **Invert graph** unchecked since the diode forward current $I_F$ is in the x-axis in this case. But in other situations, if the current is in y-axis, check the **Invert graph** checkbox.
• Enter the junction temperature as 25 °C. Click on the forward wizard icon to move on to the next step.
• Left click on top of the graph to capture the data points. In this case, for example, four data points at the current values of around 1A, 10A, 100A, and 280A are captured. Again, right click to zoom in. You can capture as many data points as desired.
• As data points are captured, red lines will appear that will connect the data points.
• Then click on the forward wizard icon to complete the data capture process. The final graph dialog window should appear as follows.

![Graph with data points and curves](image)

• To see the x and y axis values of a particular data point on the graph, place the cursor inside the graph area. The cursor image will change to a cross image, and the x and y coordinates of the cursor will be displayed at the upper right corner of the dialog window. Place the cursor on top of the curve to read the x and y axis readings.
• If there are multiple curves for different junction temperatures, repeat the same process and enter the junction temperature value for each curve accordingly. Use the drop-down menu at the upper right corner of the dialog window to show one particular curve, or to show all the curves at the same time.
• With the same process, define the reverse recovery characteristics $t_{rr}$ vs. $I_F$, $I_{rr}$ vs. $I_F$, and $Q_{rr}$ vs. $I_F$.
• Enter the **Thermal Characteristics** as:
  \[ R_{th(j-c)} = 0.6 \]
  \[ R_{th(c-s)} = 0.4 \]
• Enter the **Dimension and Weight** as:
  - Length (mm): 53
  - Width (mm): 36
  - Height (mm): 29
• Choose **Device >> Save Device** to save the device information. This completes the process of adding the diode into the database.
4.11 Renewable Energy Module

Renewable Energy Module library contains the following elements:
- Solar modules: physical model, functional model, cSi model, and thin-film model;
- Wind turbine;
- Lithium-Ion battery; and
- Super capacitor.

4.11.1 Solar Modules

4.11.1.1 Solar Module - Functional Model

Functional model represents the solar module based on \( i-v \) characteristics. Functional model of solar module is easy to use because it requires only four parameters which can be obtained on any manufacturer’s datasheet.

**Image:**

In the image, the nodes marked with the "+" and "-" signs are the positive and negative terminals. The node on the top is theoretical maximum power (in W) given the operating conditions.

While the positive and negative terminal nodes are power circuit nodes, the other nodes are all control circuit nodes.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Open Circuit Voltage</td>
<td>Voltage measured when solar cell terminals are open circuit, in V.</td>
</tr>
<tr>
<td>Short Circuit Current</td>
<td>Current measured when the solar cell terminals are short circuited, in A.</td>
</tr>
<tr>
<td>Maximum Power Voltage</td>
<td>Solar cell terminal voltage when the output power is at the maximum, in V</td>
</tr>
<tr>
<td>Maximum Power Current</td>
<td>Solar cell terminal current when the output power is at the maximum, in A</td>
</tr>
</tbody>
</table>

Using the four input parameters, the functional model will create the \( i-v \) curve of the solar cell. The figure below shows the \( i-v \) and \( p-v \) curves of a typical solar cell.

**Image:**

The curves show that the solar cell output power reaches the maximum at a specific voltage level. Many control
schemes have been proposed in the literature to track this maximum power point (so called Maximum Power Point Tracking, or MPPT) so that the solar cell output power is at the maximum.

4.11.1.2 Solar Module - Physical Model

The physical model of solar module simulates the behavior of the solar module with more accuracy because it takes into account the light intensity and temperature variation.

Image:

In the image, The nodes with the "+" and "−" signs are the positive and negative terminals. The node with the letter "S" refers to the light intensity input (in W/m\(^2\)), and The node with the letter "T" refers to the ambient temperature input (in °C). The node on the top is theoretical power (in W) given the operating conditions.

While the positive and negative terminal nodes are power circuit nodes, the other nodes are all control circuit nodes.

Attributes

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of Cells Ns</td>
<td>Number of cells (N_s) of the solar module. A solar module consists of (N_s) solar cells in series.</td>
</tr>
<tr>
<td>Standard Light Intensity S0</td>
<td>Light intensity (S_0) under the standard test conditions, in W/m(^2). The value is normally 1000 W/m(^2) in manufacturer datasheet.</td>
</tr>
<tr>
<td>Ref. Temperature Tref</td>
<td>Temperature (T_{ref}) under the standard test conditions, in °C</td>
</tr>
<tr>
<td>Series Resistance Rs</td>
<td>Series resistance (R_s) of each solar cell, in Ohm</td>
</tr>
<tr>
<td>Shunt Resistance Rsh</td>
<td>Shunt resistance (R_{sh}) of each solar cell, in Ohm</td>
</tr>
<tr>
<td>Short Circuit Current Isc0</td>
<td>Short circuit current (I_{sc0}) of each solar cell at the reference temperature (T_{ref}), in A</td>
</tr>
<tr>
<td>Saturation Current Is0</td>
<td>Diode saturation current (I_{s0}) of each solar cell at the reference temperature (T_{ref}), in A</td>
</tr>
<tr>
<td>Band Energy Eg</td>
<td>Band energy of each solar cell, in eV. It is around 1.12 for crystalline silicon, and around 1.75 for amorphous silicon.</td>
</tr>
<tr>
<td>Ideality Factor A</td>
<td>Ideality factor (A) of each solar cell, also called emission coefficient. It is around 2 for crystalline silicon, and is less than 2 for amorphous silicon.</td>
</tr>
<tr>
<td>Temperature Coefficient Ct</td>
<td>Temperature coefficient (C_t), in (A^0\text{C}) or (A^0\text{K})</td>
</tr>
<tr>
<td>Coefficient Ks</td>
<td>Coefficient (k_s) that defines how light intensity affects the solar cell temperature.</td>
</tr>
</tbody>
</table>

A solar module consists of \(N_s\) solar cells in series, and the equivalent circuit of the physical model of one solar
The equations that describe a solar cell are:

\[ i = i_{ph} - i_d - i_r \]

and

\[ i_{ph} = I_{sc0} \cdot \frac{S}{S_0} + C_i \cdot (T - T_{ref}) \]

\[ i_d = I_0 \cdot \left( \frac{qV_d}{kT} - 1 \right) \]

\[ I_0 = I_{so} \cdot \left( \frac{T}{T_{ref}} \right)^3 \cdot e^{\frac{qE_g}{kT} \left( \frac{1}{T_{ref}} - \frac{1}{T} \right)} \]

\[ i_r = \frac{V_d}{R_{sh}} \]

\[ v_d = \frac{V}{N_s} + i \cdot R_s \]

\[ T = T_a + k_s \cdot S \]

where \( q \) is the electron charge (\( q = 1.6 \times 10^{-19} \text{ C} \)); \( k \) is the Boltzmann constant (\( k = 1.3806505 \times 10^{-23} \)); \( S \) is the light intensity input; \( T_a \) is the ambient temperature input; \( v \) is the voltage across the entire solar module; and \( i \) is the current flowing out of the positive terminal of the solar module.

Some of the parameters of the physical model can be obtained from manufacturer datasheet, and the rest of the parameters can be obtained by trial-and-error. A utility tool *Solar Module (physical model)* under the Utilities
menu is provided to help obtaining the parameters from manufacturer datasheet. The interface of the tool is shown on the right.

For more details on how to use this tool to obtain the model parameters, please refer to the tutorial Tutorial - Solar Module (physical module).pdf in the "doc" sub-folder in the PSIM directory.

### 4.11.1.3 Solar Module - cSi and Thin-File Models

The solar module’s cSi (Crystalline Silicon) and Thin-Film models are developed according to EN50530 Standard. Only three parameters are needed. This is because material related data are already included in the v-i characteristic equations in these models.

**Images:**

![EN50530 (cSi) and EN50530 (thin film)](image)

In the image, the nodes marked with the "+" and "-" signs are the positive and negative terminals. The node with the letter "S" refers to the light intensity input (in W/m²), and The node with the letter "T" refers to the ambient temperature input (in °C).

While the positive and negative terminal nodes are power circuit nodes, the other nodes are all control circuit nodes.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Maximum Power</td>
<td>Solar cell maximum output power, in W.</td>
</tr>
<tr>
<td>Maximum Power Voltage</td>
<td>Solar cell terminal voltage when the output power is at the maximum, in V</td>
</tr>
<tr>
<td>Test Condition Temperature</td>
<td>Test condition temperature, in degree C.</td>
</tr>
</tbody>
</table>

The current-voltage characteristic of cSi and thin-film models equations are:

\[
I_{pv} = I_{ph} - I_0 \left( e^{\frac{V_{pv} + I_{pv}R_s}{mV_r}} - 1 \right) - (V_{pv} + I_{pv}R_s)/R_p
\]

Where,

\[
I_0 = C_0 T_{mod}^3 \frac{V_{pv}}{V_r}
\]

and

\[
V_T = \frac{kT_{mod}}{e_0}
\]

Linear temperature model for the module temperature:

\[
T_{mod} = T + \frac{c}{1000} \frac{G}{W/m^2}
\]

In the above equations:
- \( I_{pv} \) Module current
- \( I_0 \) Diode saturation current
- \( I_{ph} \) Photo current (source current)
The technology dependable parameters providing the v-i curve of this model are listed in the table below:

<table>
<thead>
<tr>
<th></th>
<th>cSi</th>
<th>Thin Film</th>
<th>Tolerance</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\frac{V_{mpp}(G=200(W/m^2))}{V_{mpp}(G=1000(W/m^2))}$</td>
<td>0.95</td>
<td>0.98</td>
<td>+/- 1%</td>
</tr>
<tr>
<td>$\frac{V_{mppSTC}}{V_{ocSTC}}$</td>
<td>0.8</td>
<td>0.72</td>
<td>&lt; 1%</td>
</tr>
<tr>
<td>$\frac{I_{mppSTC}}{I_{scSTC}}$</td>
<td>0.9</td>
<td>0.8</td>
<td>&lt; 1%</td>
</tr>
</tbody>
</table>

**PV generator model for MPPT performance tests:**

MPP to open circuit voltage ratio:

$$FF_V = \frac{V_{mppSTC}}{V_{ocSTC}}$$

MPP to short circuit current ratio:

$$FF_I = \frac{I_{mppSTC}}{I_{scSTC}}$$

Formula for the PV current as a function of PV voltage:

$$I_{pv} = I_{sc}\left(\frac{V_{pv}}{V_{ocSTC}} - 1\right)$$

Irradiance G and temperature T dependent short circuit current:

$$I_{sc} = I_{scSTC}\frac{G}{G_{STC}} \cdot [1 + \alpha \cdot (T_{pv} - T_{STC})]$$

Irradiance and temperature dependent open circuit voltage:

$$V_{OC} = V_{ocSTC} \cdot (1 + \beta \cdot (T_{pv} - T_{STC})) \left(\ln\left(\frac{G}{C_G} + 1\right) \cdot C_v - (C_R \cdot G)\right)$$

Where the temperature of the PV generator should follow the ambient conditions as follows:

$$T_{pv} = T_{amb} + T_0 + \frac{k}{1 + \tau \cdot s} \cdot G$$

where

$T_{pv}$: Computed PV generator temperature;
\[ T_{\text{amb}} \] Ambient temperature;
\[ T_0 \] Correction temperature (\( T_0 = -30^\circ\text{C} \));
\[ k \] Irradiance gain (\( k = 0.03 \text{ km}^2/\text{W} \));
\[ \tau \] Time constant (\( \tau = 5 \text{ minutes} \));
\[ \alpha \] Temperature coefficient of the current;
\[ \beta \] Temperature coefficient of the voltage;
\[ C_R, C_V, C_G \] Technology depending correction factor

Irradiance dependent current \( I_0 \) is given as:
\[
I_0 = I_{sc,STC} (1 - FF_I)^{1/1(1-FF_I)} \frac{G}{G_{STC}}
\]

Constant \( C_{AQ} \) is given as:
\[
C_{AQ} = \frac{FF_{V} - 1}{\ln(1 - FF_{I})}
\]

Voltage ratio from \( V_{MPP} \) at an irradiance of 200W/m² to \( V_{MPP} \) at an irradiance of 1000W/m² is given as:
\[
V_{L2H} = \frac{V_{MPP}|_{G=200W/m^2}}{V_{MPP}|_{G=1000W/m^2}}
\]

The parameters of the PV generator model must be set as listed in the table below:

<table>
<thead>
<tr>
<th></th>
<th>cSi</th>
<th>Thin-Film</th>
<th>Tolerance</th>
</tr>
</thead>
<tbody>
<tr>
<td>( FF_I )</td>
<td>0.8</td>
<td>0.72</td>
<td>&lt; 1%</td>
</tr>
<tr>
<td>( FF_V )</td>
<td>0.9</td>
<td>0.8</td>
<td>&lt; 1%</td>
</tr>
<tr>
<td>( C_G [W/m^2] )</td>
<td>2.514E-03</td>
<td>1.252E-03</td>
<td>-</td>
</tr>
<tr>
<td>( C_V )</td>
<td>8.593E-02</td>
<td>8.419E-02</td>
<td>-</td>
</tr>
<tr>
<td>( C_R [m^2/W] )</td>
<td>1.088E-04</td>
<td>1.476E-04</td>
<td>-</td>
</tr>
<tr>
<td>( V_{L2H} )</td>
<td>0.95</td>
<td>0.98</td>
<td>±1 %</td>
</tr>
<tr>
<td>( \alpha )</td>
<td>0.04</td>
<td>0.02</td>
<td></td>
</tr>
<tr>
<td>( \beta )</td>
<td>-0.4</td>
<td>-0.2</td>
<td></td>
</tr>
</tbody>
</table>

### 4.11.2 Wind Turbine

The image and parameter of the wind turbine are described below.

**Image:**

- **Wind Speed** \( \omega \)
- **Pitch Angle** \( \phi \)
- **Wind Turbine Shaft**

---

150 Chapter 4: Power Circuit Components
The power generated by a wind turbine can be expressed as:

\[ P = \frac{1}{2} A \cdot v_{\text{wind}}^3 \cdot \rho \cdot C_p \]

where \( A \) is the area of the rotor blade (in m\(^2\)), \( v_{\text{wind}} \) is the wind speed (in m/sec), \( \rho \) is the air density (it is approximately 1.225 kg/m\(^3\)), and \( C_p \) is the power coefficient. The power coefficient \( C_p \) is a function of the tip speed ratio \( \lambda \) and the blade pitch angle \( \beta \). It can be expressed as [Heier\(^1\)]:

\[ C_p = c_1 \cdot (c_2 - c_3 \beta - c_4 \beta^x - c_5) \cdot e^{-c_6} + c_7 \]

where \( c_1 = 0.5, c_2 = 116*\lambda', c_3 = 0.4, c_4 = 0, c_5 = 5, c_6 = 21*\lambda', c_7 = 0.01*\lambda \), and

\[ \lambda = \frac{\omega_m \cdot R_{\text{blade}}}{v_{\text{wind}}} \]

\[ \lambda' = \frac{1}{\lambda + 0.08\beta} \cdot \frac{0.035}{\beta^3 + 1} \]

where \( \omega_m \) is the rotor rotational speed (in rad/sec.) and \( R_{\text{blade}} \) is the radius of the rotor blade (in m).

The relationship between the power coefficient \( C_p \) and the tip speed ratio \( \lambda \) and the blade pitch angle \( \beta \) can be plotted in the figure below.

---

The figure shows that the power coefficient $C_p$ reaches the maximum of 0.49 when the tip speed ratio $\lambda$ is 8.18. We choose the values of $C_p$ and $\lambda$ at the maximum as the nominal values, i.e., $C_{p\text{ nom}} = 0.49$, $\lambda_{\text{nom}} = 8.18$. One way to control the wind turbine, therefore, is to maintain the tip speed ratio at or close to the nominal value so that the power that the wind turbine generates is at the maximum.

Several elements related to renewable energy applications are included here.

### 4.11.3 Lithium-Ion Battery Model

A lithium-ion battery model is provided. It comes with two images: one with the battery image, and the other with the battery cell symbol image.

**Images:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of Cells in Series</td>
<td>Number of cells $N_s$ in series of a battery pack</td>
</tr>
<tr>
<td>No. of Cells in Parallel</td>
<td>Number of cells $N_p$ in parallel of a battery pack</td>
</tr>
<tr>
<td>Voltage Derating Factor</td>
<td>Voltage derating factor $K_v$, from 0 (100% derating) to 1 (no derating)</td>
</tr>
<tr>
<td>Capacity Derating Factor</td>
<td>Capacity derating factor $K_p$, from 0 (100% derating) to 1 (no derating)</td>
</tr>
<tr>
<td>Rated Voltage</td>
<td>Rated voltage $E_{\text{rated}}$ of the battery cell, in V</td>
</tr>
<tr>
<td>Discharge Cut-off Voltage</td>
<td>Battery voltage $E_{\text{cut}}$ corresponding to the maximum capacity, in V</td>
</tr>
<tr>
<td>Rated Capacity</td>
<td>Rated capacity $Q_{\text{rated}}$ of the battery cell, in Ah</td>
</tr>
<tr>
<td>Internal Resistance</td>
<td>Internal resistance $R_{\text{battery}}$ of the battery cell, in Ohm</td>
</tr>
<tr>
<td>Full Voltage</td>
<td>Full (or maximum) voltage $E_{\text{full}}$ of the battery cell, in V</td>
</tr>
<tr>
<td>Exponential Point Voltage</td>
<td>Battery voltage $E_{\text{top}}$ at the end of the exponential region in the discharge curve, in V</td>
</tr>
</tbody>
</table>
In the images, the extra node at the top of the battery image or at the side of the battery cell symbol image is for the SOC output. It is a control circuit node.

Note that the battery parameters are all for one battery cell, while the model can be used to define a battery pack where the number of cells in series or in parallel is not 1. For a battery pack, all voltages need to be multiplied by \( N_s \cdot K_s \), all capacities by \( N_p \cdot K_p \), and the resistance by \( \frac{N_s}{N_p} \). For example, for the entire battery pack:

\[
\begin{align*}
E_{\text{rated\_total}} &= N_s \cdot K_s \cdot E_{\text{rated}} \\
E_{\text{cut\_total}} &= N_s \cdot K_s \cdot E_{\text{cut}} \\
E_{\text{full\_total}} &= N_s \cdot K_s \cdot E_{\text{full}} \\
E_{\text{top\_total}} &= N_s \cdot K_s \cdot E_{\text{top}} \\
E_{\text{nom\_total}} &= N_s \cdot K_s \cdot E_{\text{nom}} \\
Q_{\text{rated\_total}} &= N_p \cdot K_p \cdot Q_{\text{rated}} \\
Q_{\text{max\_total}} &= N_p \cdot K_p \cdot Q_{\text{max}} \\
Q_{\text{top\_total}} &= N_p \cdot K_p \cdot Q_{\text{top}} \\
Q_{\text{nom\_total}} &= N_p \cdot K_p \cdot Q_{\text{nom}} \\
R_{\text{battery\_total}} &= \frac{N_s}{N_p} \cdot R_{\text{battery}}
\end{align*}
\]

For a detailed description on how to define and use the lithium-ion battery model, please refer to the document "Tutorial - How to use Lithium-Ion battery model.pdf".

### 4.11.4 Ultracapacitor Model

Ultracapacitors are electrical energy storage devices that offer high power density and a high number of charge and discharge cycles.

**Images:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of Cells in Series</td>
<td>Number of cells in series</td>
</tr>
<tr>
<td>Number of Cells in Parallel</td>
<td>Number of cells in parallel</td>
</tr>
<tr>
<td>Capacitance per Cell</td>
<td>Nominal capacitance per cell, in F.</td>
</tr>
</tbody>
</table>
| Coefficient K
| Voltage coefficient    |
| Resistance R1           | Resistance coefficient R1, in Ohm  |
| Capacitance C1          | Capacitance coefficient C1, in F  |
Parameters $K_v$, $R_1$, and $C_1$ are associated with the capacitor response in the short term (in seconds.). Parameters $R_2$ and $C_2$ are associated with the response in the medium term (in minutes. Parameters $R_3$ and $C_3$ are associated with the response in the long term (in hundreds of minutes). The parameter $R_4$ is associated with capacitor losses due to self-discharge.

For further information on how to use the model, please refer to the tutorial "Tutorial - Ultracapacitor model.pdf".

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Resistance $R_2$</td>
<td>Resistance coefficient $R_2$, in Ohm</td>
</tr>
<tr>
<td>Capacitance $C_2$</td>
<td>Capacitance coefficient $C_2$, in F</td>
</tr>
<tr>
<td>Resistance $R_3$</td>
<td>Resistance coefficient $R_3$, in Ohm</td>
</tr>
<tr>
<td>Capacitance $C_3$</td>
<td>Capacitance coefficient $C_3$, in F</td>
</tr>
<tr>
<td>Resistance $R_4$</td>
<td>Resistance coefficient $R_4$, in Ohm.</td>
</tr>
<tr>
<td>Maximum Voltage</td>
<td>Maximum voltage rating per cell, in V</td>
</tr>
<tr>
<td>Initial Voltage</td>
<td>Initial capacitor voltage per cell, in V</td>
</tr>
</tbody>
</table>
This chapter provides descriptions for the components in PSIM’s element library.

5.1 Transfer Function Blocks

A transfer function block is expressed in polynomial form as:

\[ G(s) = k \cdot \frac{B_n \cdot s^n + \ldots + B_2 \cdot s^2 + B_1 \cdot s + B_0}{A_n \cdot s^n + \ldots + A_2 \cdot s^2 + A_1 \cdot s + A_0} \]

Two types of transfer function blocks are provided: one with zero initial values (the element is called \textit{s-domain Transfer Function} in the PSIM library) and the other with initial values as input parameters (called \textit{s-domain Transfer Function (initial value)} in the PSIM library).

\[ G(s) = \frac{\text{Coefficients of the numerator (from } B_n \text{ to } B_0)}{\text{Coefficients of the denominator (from } A_n \text{ to } A_0)} \]

\[ \text{Initial Values } x_n \ldots x_1 \]

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Order n</td>
<td>Order n of the transfer function</td>
</tr>
<tr>
<td>Gain</td>
<td>Gain k of the transfer function</td>
</tr>
<tr>
<td>Coeff. ( B_n \ldots B_0 )</td>
<td>Coefficients of the numerator (from ( B_n ) to ( B_0 ))</td>
</tr>
<tr>
<td>Coeff. ( A_n \ldots A_0 )</td>
<td>Coefficients of the denominator (from ( A_n ) to ( A_0 ))</td>
</tr>
<tr>
<td>Initial Values ( x_n \ldots x_1 )</td>
<td>Initial values of the state variables ( x_n ) to ( x_1 ) (for the element \textit{s-domain Transfer Function (initial value)} only)</td>
</tr>
</tbody>
</table>

Let \( Y(s) = G(s) \cdot U(s) \) where \( Y(s) \) is the output and \( U(s) \) is the input, we can convert the s-domain expression into the differential equation form as follows:

\[
\begin{bmatrix}
\frac{dx_1}{dt} \\
\frac{dx_2}{dt} \\
\vdots \\
\frac{dx_n}{dt}
\end{bmatrix} =
\begin{bmatrix}
0 & 0 & 0 & \ldots & 0 & -A_n/A_n \\
1 & 0 & 0 & \ldots & 0 & -A_1/A_n \\
0 & 1 & 0 & \ldots & 0 & -A_2/A_n \\
\vdots & \vdots & \vdots & \ldots & \vdots & \vdots \\
0 & 0 & 0 & \ldots & 1 & -A_{n-1}/A_0
\end{bmatrix}
\begin{bmatrix}
x_1 \\
x_2 \\
\vdots \\
x_n
\end{bmatrix} +
\begin{bmatrix}
B_0 - A_0 \cdot B_n/A_n \\
B_1 - A_1 \cdot B_n/A_n \\
B_2 - A_2 \cdot B_n/A_n \\
\vdots \\
B_{n-1} - A_{n-1} \cdot B_n/A_n
\end{bmatrix} \cdot u
\]

The output equation in the time domain can be expressed as:

\[ y = x_n + k \cdot \frac{B_n}{A_n} \cdot u \]

The initial values of the state variables \( x_n \) to \( x_1 \) can be specified as the inputs in the element \textit{s-domain Transfer Function (initial value)}.

\[ y = x_n + k \cdot \frac{B_n}{A_n} \cdot u \]

Example:

The following is a second-order transfer function:
In PSIM, the specification will be:

<table>
<thead>
<tr>
<th>Order n</th>
<th>2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>1.5</td>
</tr>
<tr>
<td>Coeff. $B_n...B_o$</td>
<td>0. 0. 400.e3</td>
</tr>
<tr>
<td>Coeff. $A_n...A_o$</td>
<td>1. 1200. 400.e3</td>
</tr>
</tbody>
</table>

### 5.1.1 Proportional Controller

The output of a proportional (P) controller is equal to the input multiplied by a gain.

**Image:**

```
X
```

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the transfer function</td>
</tr>
</tbody>
</table>

### 5.1.2 Integrator

There are three types of integrators: regular integrator, external resettable integrator, and internal resettable integrator.

**Images:**

Regular Integrator

```
∫
```

External Resettable Integrator

```
∫
```

Internal Resettable Integrator

```
∫
```

**Attributes:**

For **Regular Integrator:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Time Constant</td>
<td>Time constant $T$ of the integrator, in sec.</td>
</tr>
<tr>
<td>Initial Output Value</td>
<td>Initial value of the output</td>
</tr>
</tbody>
</table>

For **External Resettable Integrator:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Time Constant</td>
<td>Time constant $T$ of the integrator, in sec.</td>
</tr>
<tr>
<td>Initial Output Value</td>
<td>Initial value of the output</td>
</tr>
<tr>
<td>Reset Flag</td>
<td>Reset flag (0: edge reset; 1: level reset)</td>
</tr>
</tbody>
</table>

$$G(s) = 1.5 \cdot \frac{400.e^3}{s^2 + 1200 \cdot s + 400.e^3}$$
For **Internal Resettable Integrator**:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Time Constant</td>
<td>Time constant $T$ of the integrator, in sec.</td>
</tr>
<tr>
<td>Initial Output Value</td>
<td>Initial value of the output</td>
</tr>
<tr>
<td>Lower Output Limit</td>
<td>Lower limit of the output</td>
</tr>
<tr>
<td>Upper Output Limit</td>
<td>Upper limit of the output</td>
</tr>
</tbody>
</table>

The transfer function of an integrator is:

$$G(s) = \frac{1}{sT}$$

The Bode plot of the amplitude $|G|$ and the phase angle $\Phi$ of the integrator is shown as below:

The output of the external resettable integrator can be reset by an external control signal (at the bottom of the block). For the edge reset (reset flag = 0), the integrator output is reset to zero at the rising edge of the control signal. For the level reset (reset flag = 1), the integrator output is reset to zero as long as the control signal is high (1).

The output of the internal resettable integrator is reset to 0 when the output reaches either the lower limit or the upper limit. It works in the same way as the external resettable integrator with the edge reset, except that in this case users do not need to set up the external reset circuit.

When a limiter is connected to the integrator output, anti-windup is implemented automatically.

**Example:**

The following circuit illustrates the use of the resettable integrator. The input of the integrator is a dc quantity. The control input of the integrator is a pulse waveform which resets the integrator output at the end of each cycle. The reset flag is set to 0.
5.1.3 Differentiator

The transfer function of a differentiator is:

\[ G(s) = sT \]

A differentiator is calculated as follows:

\[ v_o(t) = T \cdot \frac{v_{in}(t) - v_{in}(t-\Delta t)}{\Delta t} \]

where \( \Delta t \) is the simulation time step, \( v_{in}(t) \) and \( v_{in}(t-\Delta t) \) are the input values at the present and the previous time step.

Since sudden changes of the input will generate spikes at the output, it is recommended that a low-pass filter be placed at the input of the differentiator.

5.1.4 Proportional-Integral Controller

A proportional-integral (PI) controller is defined as below.

The transfer function of a PI controller is defined as:

\[ G(s) = k \cdot \frac{1 + sT}{sT} \]

The Bode plot of the amplitude \(|G|\) and the phase angle \(\Phi\) of the PI controller is shown as below:

When a limiter is connected to the PI output, anti-windup is implemented automatically.
5.1.5 Single-Pole Controller

A single-pole controller is a proportional controller with a pole. It is defined as below.

\[ G(s) = k \cdot \frac{\omega_c}{s + \omega_c} \]

where \( \omega_c = 2\pi f_c \).

The Bode plot of the amplitude \(|G|\) and the phase angle \(\Phi\) of the single-pole controller is shown as below:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain ( k ) of the controller</td>
</tr>
<tr>
<td>Pole Frequency</td>
<td>Frequency of the pole ( f_c ), in Hz</td>
</tr>
</tbody>
</table>

5.1.6 Modified PI Controller

A modified PI controller (Type-2) consists of a PI with a pole.

\[ G(s) = k \cdot \frac{1}{sT_c} \cdot \frac{1}{1 + sT_c} \]

where \( T_c = \frac{1}{\omega_c} \) and \( \omega_c = 2\pi f_c \).

The Bode plot of the amplitude \(|G|\) and the phase angle \(\Phi\) of the PI controller is shown as below:
When a limiter is connected to the PI output, anti-windup is implemented automatically.

### 5.1.7 Type-3 Controller

A Type-3 controller consists of two zeros and two poles.

**Image:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the PI controller</td>
</tr>
<tr>
<td>Frequency $fz_1$</td>
<td>Frequency $f_{z_1}$ of the first zero, in Hz</td>
</tr>
<tr>
<td>Frequency $fz_2$</td>
<td>Frequency $f_{z_2}$ of the second zero, in Hz</td>
</tr>
<tr>
<td>Frequency $fp_1$</td>
<td>Frequency $f_{p_1}$ of the first pole, in Hz</td>
</tr>
<tr>
<td>Frequency $fp_2$</td>
<td>Frequency $f_{p_2}$ of the second pole, in Hz</td>
</tr>
</tbody>
</table>

The transfer function of a Type-3 controller is defined as:

$$G(s) = k \cdot \frac{1 + sT_{z_1}}{sT_{z_1}} \cdot \frac{1 + sT_{z_2}}{(1 + sT_{p_1}) \cdot (1 + sT_{p_2})}$$

where $T_{z_1} = \frac{1}{2\pi f_{z_1}}$, $T_{z_2} = \frac{1}{2\pi f_{z_2}}$, $T_{p_1} = \frac{1}{2\pi f_{p_1}}$, and $T_{p_2} = \frac{1}{2\pi f_{p_2}}$.

The Bode plot of the amplitude $|G|$ and the phase angle $\Phi$ of the Type-3 controller is shown as below:

When a limiter is connected to the controller output, anti-windup is implemented automatically.
5.1.8  Built-in Filter Blocks

Four second-order filters and one first-order filter are provided as built-in blocks in PSIM.

Images:

<table>
<thead>
<tr>
<th>2nd-order low-pass</th>
<th>2nd-order high-pass</th>
<th>2nd-order band-pass</th>
<th>2nd-order band-stop</th>
<th>1st-order low-pass</th>
</tr>
</thead>
</table>

Attributes for second-order filters:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$</td>
</tr>
<tr>
<td>Damping Ratio</td>
<td>Damping ratio $\xi$</td>
</tr>
<tr>
<td>Cut-off Frequency</td>
<td>Cut-off frequency $f_c$ ($f_c = \frac{\omega_c}{2\pi}$) for low-pass and high-pass filters, in Hz</td>
</tr>
<tr>
<td>Center Frequency</td>
<td>Center frequency $f_o$ ($f_o = \frac{\omega_o}{2\pi}$) for band-pass and band-stop filter, in Hz</td>
</tr>
<tr>
<td>Passing Band; Stopping Band</td>
<td>Frequency width $f_b$ ($f_b = \frac{B}{2\pi}$) of the passing/stopping band for band-pass/band-stop filters, in Hz</td>
</tr>
</tbody>
</table>

Attributes for first-order low-pass filter:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$</td>
</tr>
<tr>
<td>Cut-off Frequency</td>
<td>Cut-off frequency $f_c$ ($f_c = \frac{\omega_c}{2\pi}$) of the low-pass filter, in Hz</td>
</tr>
</tbody>
</table>

The transfer function of these filters are listed below.

For second-order low-pass filter:

$$G(s) = k \cdot \frac{\omega_c^2}{s^2 + 2\xi \omega_c s + \omega_c^2}$$

For second-order high-pass filter:

$$G(s) = k \cdot \frac{s^2}{s^2 + 2\xi \omega_c s + \omega_c^2}$$

For second-order band-pass filter:

$$G(s) = k \cdot \frac{B \cdot s}{s^2 + B \cdot s + \omega_o^2}$$

For second-order band-stop filter:

$$G(s) = k \cdot \frac{s^2 + \omega_o^2}{s^2 + B \cdot s + \omega_o^2}$$

For first-order low-pass filter:

$$G(s) = k \cdot \frac{\omega_c}{s + \omega_c}$$
5.2 Computational Function Blocks

5.2.1 Summer

The input of a one-input summer or two-input summer can be either a scalar or a vector. The input of a three-input summer can only be a scalar.

Images:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain ( k_i )</td>
<td>Gain ( k_i ) for the ( i )th input</td>
</tr>
</tbody>
</table>

For the three-input summer, the input with a dot is the first input.

If the inputs are scalar, the output of a summer with \( n \) inputs is defined as:

\[ V_o = k_1 V_1 + k_2 V_2 + \ldots + k_n V_n \]

If the input is a vector, the output of a two-input summer will also be a vector, which is defined as:

\[
\begin{align*}
V_1 &= [a_1 \ a_2 \ldots a_n] \\
V_2 &= [b_1 \ b_2 \ldots b_n] \\
V_o &= V_1 + V_2 = [a_1+b_1 \ a_2+b_2 \ldots \ a_n+b_n]
\end{align*}
\]

The output of a one-input summer, however, will still be a scalar which is equal to the summation of the input vector elements, that is, \( V_o = a_1 + a_2 + \ldots + a_n \).

5.2.2 Multiplier and Divider

The output of a multipliers or divider is equal to the multiplication or division of two inputs.

Images:

For the divider, the dotted node is for the numerator input.

The input of a multiplier can be either a vector or a scalar. If the two inputs are vectors, their dimensions must be equal. Let the two inputs be:

\[
\begin{align*}
V_1 &= [a_1 \ a_2 \ldots a_n] \\
V_2 &= [b_1 \ b_2 \ldots b_n]
\end{align*}
\]

The output, which is a scalar, will be:

\[
V_o = V_1 \cdot V_2^T = a_1 b_1 + a_2 b_2 + \ldots + a_n b_n
\]
5.2.3 **Square-Root Block**

A square-root function block calculates the square root of the input.

**Image:**

![Square Root Block Diagram]

5.2.4 **Exponential/Power/Logarithmic Function Blocks**

The images and attributes of these function blocks are shown below.

**Images:**

![Exponential, Power, LOG, LOG10 Block Diagrams]

**Attributes (for exponential and power blocks):**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Coefficient $k_1$</td>
<td>Coefficient $k_1$</td>
</tr>
<tr>
<td>Coefficient $k_2$</td>
<td>Coefficient $k_2$</td>
</tr>
</tbody>
</table>

The output of an exponential function block is defined as:

$$ V_o = k_1 \cdot k_2^{V_{in}} $$

For example, if $k_1 = 1$, $k_2 = 2.718281828$, and $V_{in} = 2.5$, then $V_o = e^{2.5}$ where $e$ is the base of the natural logarithm.

The output of a power function block is defined as:

$$ V_o = k_1 \cdot V_{in}^{k_2} $$

The function block LOG gives the natural logarithm (base $e$) of the input, and the block LOG10 gives the common logarithm (base 10) of the input.

5.2.5 **Root-Mean-Square Block**

A root-mean-square function block calculates the RMS value of the input over a period specified by the base frequency $f_b$. The output is defined as:

$$ V_{rms} = \sqrt{\frac{1}{T_0} \int_0^T V_{in}^2(t)dt} $$

where $T = 1/f_b$. The output is only updated at the beginning of each period.

**Image:**

![RMS Block Diagram]

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Base frequency</td>
<td>Base frequency $f_b$ in Hz</td>
</tr>
</tbody>
</table>
5.2.6 Absolute and Sign Function Blocks

An absolute value function block gives the absolute value of the input. A sign function block gives the sign of the input, i.e., the output is 1 if the input is positive, 0 if the input is 0, and -1 if the input is negative.

Images:

<table>
<thead>
<tr>
<th>Absolute</th>
<th>Sign</th>
</tr>
</thead>
<tbody>
<tr>
<td>(</td>
<td>x</td>
</tr>
</tbody>
</table>

5.2.7 Trigonometric Functions

The following trigonometric functions are provided: sine (sin), cosine (cos), arc-sine (sin\(^{-1}\)), arc-cosine (cos\(^{-1}\)), tangent (tan), arc-tangent (tg\(^{-1}\)), and arc-tangent 2 (atan2).

The output is equal to the corresponding trigonometric function of the input. For the sin, cos, and tan blocks, the input can be in degree, radian, or per unit. and for the arcsin, arccos, and arctangent blocks, the output can be in degree, radian, or per unit.

Images:

<table>
<thead>
<tr>
<th>Input in deg.</th>
<th>sin (\text{deg}^\circ)</th>
<th>sin(^{-1}) (\text{deg}^\circ)</th>
<th>cos (\text{deg}^\circ)</th>
<th>cos(^{-1}) (\text{deg}^\circ)</th>
<th>tan (\text{deg}^\circ)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Input in rad.</td>
<td>(r\text{sin})</td>
<td>(r\text{cos})</td>
<td>(r\text{sin})</td>
<td>(r\text{cos})</td>
<td></td>
</tr>
<tr>
<td>Input in per unit</td>
<td>(u\text{sin})</td>
<td>(u\text{cos})</td>
<td>(u\text{sin})</td>
<td>(u\text{cos})</td>
<td></td>
</tr>
</tbody>
</table>

If the input of a block has the letter "r", it is in radian. If the input has the letter "u", it is in per unit. Otherwise it is in deg.

In the arctangent and arctangent 2 blocks, the input node marked with \(x\) is the real part, and the other input node marked with \(y\) is the imaginary part. If the output has the letter "u", the output is in per unit.

The output of the arctangent and arctangent 2 blocks is the inverse tangent of the ratio between the imaginary part \(y\) and the real part \(x\), i.e. \(\theta = \text{tg}^{-1}\left(\frac{y}{x}\right)\). The output of the arctangent block is in degree, and the range is from 0 to 360\(^\circ\). On the other hand, the output of the arctangent 2 block is in radian, and the range is from -\(\pi\) to +\(\pi\). The arctangent 2 block behaves in the same way as the function atan2(y,x) in the C language.

5.2.8 Fast Fourier Transform Block

A Fast Fourier Transform block calculates the fundamental component of the input signal. The FFT algorithm is based on the radix-2/decimation-in-frequency method. The number of sampling points within one fundamental period should be \(2^N\) (where \(N\) is an integer). The maximum number of sampling points allowed is 1024.

The output gives the peak amplitude and the phase angle of the input fundamental component. The output voltage (in complex form) is defined as:
The dotted node of the block refers to the output of the amplitude. Note that the phase angle output has been internally adjusted such that a sine function \( V_m \cdot \sin(\omega t) \) will give a phase angle output of 0.

Note that the FFT block only works if the input signal contains dc, the fundamental component, and harmonics of the fundamental components (with the frequencies at multiple integer times of the fundamental frequency). If the input signal contains another component that is not multiple integer of the fundamental frequency, the FFT block will not give the correct result.

Also, the FFT block only measures the fundamental component, not any other harmonics. For example, if the input signal contains 60 Hz (fundamental) and 180 Hz, if the parameter "Fundamental Frequency" is set to 180, the FFT block output will be incorrect.

**Example:**

In the circuit below, the voltage \( V_{in} \) contains a fundamental component \( v_1 \) (100 V at 60 Hz), a 5th harmonic voltage \( v_5 \) (25 V at 300 Hz), and a 7th harmonic \( v_7 \) (25 V at 420 Hz). After one cycle, the FFT block output reaches the steady state with the amplitude of 100 V and the phase angle of 0°.

### 5.2.9 Maximum/Minimum Function Block

A maximum/minimum function block detects the maximum or minimum of the inputs.
5.3 Other Function Blocks

5.3.1 Comparator

The output of a comparator is high when the positive input is higher than the negative input. When the positive input is lower, the output is zero. If the two input are equal, the output is undefined and it will keep the previous value.

Image:

Note that the comparator image is similar to that of the op. amp. For the comparator, the noninverting input is at the upper left and the inverting input is at the lower left. For the op. amp., however, it is the opposite.

5.3.2 Limiters

Four types of limiters are provided to limit the amplitude of a signal: lower/upper limiter, lower limiter, upper limiter, and range limiter.

Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Lower Limit</td>
<td>Lower limit $V_{lower}$ of the limiter</td>
</tr>
<tr>
<td>Upper Limit</td>
<td>Upper limit $V_{upper}$ of the limiter</td>
</tr>
</tbody>
</table>

For a lower/upper limiter, or lower limiter, or upper limiter, the output of the limiter is clamped to the upper or lower limit whenever the input exceeds the limiter range. If the input is within the limit, the output is equal to the input.

A range limiter limits the output $v_o$ between the lower limit and the upper limit, that is:

$$V_{lower} \leq v_o < V_{upper}$$

Let the range of the upper limit and the lower limit be $V_{range}$. When the output is equal to or greater than the upper limit, the output is subtracted by the range $V_{range}$ until it is within the range. When the output is below the lower limit, it is added by range $V_{range}$ until it is within the range. When the input is within the limit, the output is equal to the input.
5.3.3 Gradient (dv/dt) Limiter

A gradient (dv/dt) limiter limits the rate of change of the input. If the rate of change is within the limit, the output is equal to the input.

![Image](image)

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dv/dt Limit</td>
<td>Limit of the rate of change (dv/dt) of the input</td>
</tr>
</tbody>
</table>

5.3.4 Trapezoidal and Square Blocks

Trapezoidal waveform blocks and square waveform blocks are specific types of lookup tables: the output and the input relationship is either a trapezoidal or a square waveform.

![Images](images)

For the trapezoidal waveform block:

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rising Angle theta</td>
<td>Rising angle $\theta$, in deg.</td>
</tr>
<tr>
<td>Peak Value</td>
<td>Peak value $V_{pk}$ of the waveform</td>
</tr>
</tbody>
</table>

For the square waveform block:

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Pulse Width (deg.)</td>
<td>Pulse width $\theta$ in half cycle, in deg.</td>
</tr>
</tbody>
</table>

The waveforms of these two blocks are shown below. Note that the input $v_{in}$ is in deg., and can be in the range of $-360^\circ$ to $360^\circ$. Both waveforms are half-wave and quarter-wave symmetrical.

![Images](images)
### 5.3.5 Sampling/Hold Block

A sampling/hold block samples the input when the control signal changes from low to high (from 0 to 1), and holds this value until the next point is sampled.

**Image:**

![Sampling/Hold Block Diagram]

The difference between this block and the zero-order hold block (ZOH) in Digital Control Module is that this block is treated as a continuous element and sampling moments can be controlled externally; whereas the zero-order hold block is a discrete element and the sampling moments are fixed and of equal distance.

For a discrete system, the zero-order hold block should be used.

**Example:**

In this example, a sinusoidal input is sampled. The control signal is a square wave voltage source with an amplitude of 1.

### 5.3.6 Round-Off Block

The image of a round-off block is shown below:

**Image:**

![Round-Off Block Diagram]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of Digits</td>
<td>No. of digits $N$ after the decimal point</td>
</tr>
<tr>
<td>Truncation Flag</td>
<td>Truncation flag (1: truncation; 0: round-off)</td>
</tr>
</tbody>
</table>

Let the input of the round-off block be $V_{in}$. The input is first scaled based on the following expression:

$$V_{in,new} = V_{in} \cdot 10^N$$

If the truncation flag is 1, the output will be equal to $V_{in,new}$ truncated, and then divided by $10^N$. Otherwise, the output will be equal to $V_{in,new}$ rounded off to the nearest integer, and then divided by $10^N$.

**Examples:**

If $V_{in} = 34.5678$, $N = 0$, truncation flag = 0, then we have the output $V_{out} = 35$. Similarly, if $V_{in} = 34.5678$, $N = 0$, truncation flag = 1, then $V_{out} = 34$.

If $V_{in} = 34.5678$, $N = 1$, truncation flag = 1, then $V_{out} = 34.5$. If $V_{in} = 34.5678$, $N = -1$, truncation flag = 1, then $V_{out} = 30$. 
5.3.7 Time Delay Blocks

Two types of time delay blocks are provided: one with arbitrary delay time, and the other with only one simulation time step.

Images:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Delay Time</td>
<td>Delay time, in sec. (for the Time Delay block only)</td>
</tr>
</tbody>
</table>

A time delay block delays the input signal by a specified amount of time interval. The input signal can be an analog signal or logic signal. For example, it can be used to model the propagation delay of a logic element.

A unit time delay block delays the input signal by just one simulation time step. If the simulation time step is changed, the delay time will be changed accordingly.

Note that the difference between the unit time delay block and the unit delay block in Digital Control Module is that this block is a continuous element and the delay time is one simulation time step; whereas the unit delay block is a discrete element and the delay time is equal to the sampling period.

For a discrete system, the unit delay block should be used.

5.3.8 Multiplexer

The output of a multiplexer is equal to a selected input depending on the control signal. Two types of multiplexers are provided: One with binary control inputs, and the other with individual control inputs.

Images:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>d1</td>
</tr>
<tr>
<td>d0</td>
<td>d1</td>
</tr>
</tbody>
</table>

In the images, d0...d7 are the data inputs; and s0..s2 are the control inputs. The truth tables of the multiplexers are as follows.

For multiplexers with binary control inputs:

<table>
<thead>
<tr>
<th>2-Input</th>
<th>4-Input</th>
<th>8-Input</th>
</tr>
</thead>
<tbody>
<tr>
<td>s0</td>
<td>s1</td>
<td>s0</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
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<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>
For multiplexers with individual control inputs:

<table>
<thead>
<tr>
<th>3-Input</th>
<th>4-Input</th>
</tr>
</thead>
<tbody>
<tr>
<td>s1</td>
<td>s2</td>
</tr>
<tr>
<td>s0</td>
<td>s1</td>
</tr>
<tr>
<td>Y</td>
<td>s0</td>
</tr>
<tr>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>d0</td>
<td>d0</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>d1</td>
<td>d1</td>
</tr>
<tr>
<td>otherwise</td>
<td>otherwise</td>
</tr>
</tbody>
</table>

Note that the data input could be either an analog or digital signal.

**Example:**

The following circuit selects the maximum value out of two inputs. When \( V_a \) is greater than \( V_b \), the comparator output will be 1, and \( V_o = V_a \). Otherwise \( V_o = V_b \).

![Circuit Diagram]

5.3.9 **THD Block**

The total harmonic distortion (THD) of an ac waveform that contains both the fundamental and harmonic components is defined as:

\[
THD = \frac{V_h}{V_1} = \sqrt{\frac{V_{rms}^2 - V_1^2}{V_1^2}}
\]

where \( V_1 \) is the fundamental component (rms), \( V_h \) is the harmonic rms value, and \( V_{rms} \) is the overall rms value of the waveform. The THD block is modelled as shown below.

![THD Block Diagram]

A second-order band-pass filter is used to extract the fundamental component. The center frequency and the passing band of the band-pass filter need to be specified.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fundamental Frequency</td>
<td>Fundamental frequency of the input, in Hz</td>
</tr>
<tr>
<td>Passing Band</td>
<td>Passing band of the band-pass filter, in Hz</td>
</tr>
</tbody>
</table>
Example:

In the single-phase thyristor circuit below, a THD block is used to measure the THD of the input current. The delay angle of the thyristor bridge is chosen as 30°. For the THD block, the fundamental frequency is set at 60 Hz and the passing band of the filter is set at 20 Hz. The simulation results are shown on the right.

One of the THD block output is the input current fundamental component $i_{s1}$. By comparing the phase difference between the input voltage $v_s$ and the current $i_{s1}$, one can calculate the input displacement power factor. This, together with the THD value, can be used to calculate the input power factor.

5.3.10 Space Vector PWM

A space vector PWM block is used in a carrier-wave based PWM scheme. It changes the 3-phase modulation signals such that the PWM modulator gain is similar to that of a digitally implemented space vector PWM.

5.4 Logic Components

5.4.1 Logic Gates

Basic logic gates are AND, OR, XORGATE (exclusive-OR), NOT, NAND, and NOR gates.
5.4.2 Set-Reset Flip-Flop

There are two types of set-reset flip-flops. One is edge-triggered and the other is level-triggered.

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Trigger Flag</td>
<td>Trigger flag (0: edge-triggered; 1: level-triggered)</td>
</tr>
</tbody>
</table>

An edge-triggered flip-flop only changes the states at the rising edge of the set/reset input. The truth table of an edge-triggered flip-flop is:

<table>
<thead>
<tr>
<th>S</th>
<th>R</th>
<th>Q</th>
<th>Q</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>no change</td>
<td></td>
</tr>
<tr>
<td>0</td>
<td>↑</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>↑</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>↑</td>
<td>↑</td>
<td>not used</td>
<td></td>
</tr>
</tbody>
</table>

A level-triggered flip-flop, on the other hand, changes the states based on the input level. The truth table of a level-triggered set-reset flip-flop is:

<table>
<thead>
<tr>
<th>S</th>
<th>R</th>
<th>Q</th>
<th>Q</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>no change</td>
<td></td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>not used</td>
<td></td>
</tr>
</tbody>
</table>

5.4.3 J-K Flip-Flops

Two types of J-K flip-flops are provided: One without the set/reset inputs, and the other with the set input (S̅) and reset input (R̅). For the element without the set and reset inputs, it is assumed that both set/reset inputs are high (1).

**Images:**

A J-K flip-flop is positive edge triggered, and the truth table is:

<table>
<thead>
<tr>
<th>S</th>
<th>R</th>
<th>J</th>
<th>K</th>
<th>Clock</th>
<th>Q</th>
<th>Q</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>x</td>
<td>x</td>
<td>x</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>0</td>
<td>0</td>
<td>↑</td>
<td>no change</td>
<td></td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>0</td>
<td>1</td>
<td>↑</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
<td>0</td>
<td>↑</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>↑</td>
<td>Toggle</td>
<td></td>
</tr>
</tbody>
</table>
Chapter 5: Control Circuit Components

5.4.4 D Flip-Flops

Two types of D flip-flops are provided: One without the set/reset inputs, and the other with the set input (S) and reset input (R). For the element without the set and reset inputs, it is assumed that both set/reset inputs are high (1).

Images:

A D flip-flop is positive edge triggered, and the truth table is:

<table>
<thead>
<tr>
<th>S</th>
<th>R</th>
<th>D</th>
<th>Clock</th>
<th>Q</th>
<th>Q</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>x</td>
<td>x</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>0</td>
<td>↑</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>1</td>
<td>↑</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>

5.4.5 Monostable Multivibrator

In a monostable multivibrator, the positive (or negative) edge of the input signal triggers the monostable. A pulse, with the specified pulse width, will be generated at the output.

The output pulse width can be either fixed or adjusted through another input variable. The latter type of monostables is referred to as controlled monostables. Its on-time pulse width, in second, is determined by the control input.

Images:

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Pulse Width</td>
<td>On-time pulse width, in sec.</td>
</tr>
</tbody>
</table>

The input node at the bottom of the controlled monostable block is for the pulse width input.
5.4.6 Pulse Width Counter

A pulse width counter measures the width of a pulse. The rising edge of the input activates the counter. At the falling edge of the input, the output gives the width of the pulse (in sec.). During the interval of two falling pulse edges, the pulse width counter output remains unchanged.

Image:

5.4.7 Up/Down Counter

An up/down counter increments or decrements by 1 at each rising edge of the clock.

Image:

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of Bits</td>
<td>Number of bits N</td>
</tr>
</tbody>
</table>

When the Up/Down input is 0, the counter decrements, and when the Up/Down input is 1, the counter increments.

The Reset input resets the counter to 0 when it is high (1). The Preset Enable input sets the counter to the preset value when it is high.

The truth table of the counter is:

<table>
<thead>
<tr>
<th>Up/Down</th>
<th>Preset Enable</th>
<th>Reset</th>
<th>Clock</th>
<th>Action</th>
</tr>
</thead>
<tbody>
<tr>
<td>x</td>
<td>0</td>
<td>0</td>
<td>x</td>
<td>No count</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>0</td>
<td>↑</td>
<td>Count up</td>
</tr>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>↑</td>
<td>Count down</td>
</tr>
<tr>
<td>x</td>
<td>1</td>
<td>0</td>
<td>x</td>
<td>Preset</td>
</tr>
<tr>
<td>x</td>
<td>x</td>
<td>0</td>
<td>x</td>
<td>Reset</td>
</tr>
<tr>
<td>x</td>
<td>x</td>
<td>1</td>
<td>x</td>
<td>Reset</td>
</tr>
</tbody>
</table>

x: Do not care
5.4.8 A/D and D/A Converters

A/D and D/A converters perform analog-to-digital and digital-to-analog conversion. Both 8-bit and 10-bit converters are provided.

Images:

Let \( N \) be the number of bits. The output of the A/D converter is calculated as:

\[
V_o = \frac{2^N}{V_{ref}} \cdot V_{in}
\]

The output will be clamped to \( 2^N - 1 \).

For example, if \( V_{ref} = 5 \text{ V}, V_{in} = 3.2 \text{ V}, N = 8 \) bits, then

\[
V_o = \frac{256}{5} \cdot 3.2 = 163.84 = 10100011 \text{ (binary)}
\]

The output of the D/A converter is calculated as:

\[
V_o = \frac{V_{ref}}{2^N} \cdot V_{in}
\]

For example, if \( V_{ref} = 5 \text{ V}, V_{in} = 10100011 \text{ (binary)} = 163, N = 8 \) bits, then

\[
V_o = \frac{163}{256} \cdot 5 = 3.1836
\]

5.5 Digital Control Module

The Digital Control Module is an add-on module to the basic PSIM program. It provides discrete elements, such as zero-order hold, z-domain transfer function blocks, digital filters, etc., for digital control system simulation.

In contrary to a s-domain circuit which is continuous, a z-domain circuit is discrete, and the calculation is only performed at the discrete sampling points. There is no calculation between two sampling points.

5.5.1 Motor Control Blocks

Elements in this subdivision are for digitally controlled motor drive systems.

5.5.1.1 Ramp Control

This block produces a ramp output when the input has a step change.

Image:
### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Upper Limit</td>
<td>Maximum ramp output, in per unit.</td>
</tr>
<tr>
<td>Lower Limit</td>
<td>Minimum ramp output, in per unit.</td>
</tr>
<tr>
<td>Step Duration</td>
<td>Number of sampling period N at each step. It must be an integer equal or greater than 1.</td>
</tr>
<tr>
<td>Step Size</td>
<td>The maximum ramp step change Vstep at the output, in per unit.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

In the image, the output node with a small dot is the ramp output, and the other output node is the flag indicating that the output equals the input.

If the input is greater than the output, the output will increment by Vstep after a duration of N sampling periods. If the input is less than output, the output will decrement by Vstep after a duration of N sampling periods. If the input is equal to the output, the flag will be set to 1. Otherwise it will be 0.

#### 5.5.1.2 Ramp Generator

This block generates a ramp output based on input settings.

**Image:**

![Image of Ramp Generator](image.png)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Base Frequency</td>
<td>Base frequency fb, in Hz.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

In the image, the first input is the Gain; the second input is the Offset; and the third input is the desired frequency freq for output ramp.

The ramp output waveform is shown below.

![Ramp Output Waveform](image.png)

The output ramp frequency is the multiple of the input value and the base frequency fb. The output range is limited from -1 to +1. Therefore, the range of Offset and Gain must be limited as: Offset + Gain <= 1.
5.5.1.3 Sliding Mode Observer (PMSM)

The function of this sliding mode observer block is to estimate the rotor position of a permanent-magnet synchronous motor (PMSM). This block behaves in the same way as the SMOPOS block of the TI DMC Library.

**Image:**

![Image of Sliding Mode Observer block](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Base Voltage</td>
<td>Motor base phase voltage, in V</td>
</tr>
<tr>
<td>Base Current</td>
<td>Motor base phase current, in A</td>
</tr>
<tr>
<td>Stator Resistance</td>
<td>Motor stator resistance, in Ohm</td>
</tr>
<tr>
<td>Stator Inductance</td>
<td>Motor stator inductance, in H</td>
</tr>
<tr>
<td>Gain Kslide</td>
<td>Sliding mode control gain</td>
</tr>
<tr>
<td>Gain Kslf</td>
<td>Sliding mode control filter gain</td>
</tr>
<tr>
<td>Coefficient E0</td>
<td>Coefficient to limit the error integral saturation. The default value is 0.5.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

5.5.1.4 Speed Calculator

This block calculates the motor speed based on the rotor angle theta.

**Image:**

![Image of Speed Calculator block](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Base Frequency fb</td>
<td>Base frequency, in Hz</td>
</tr>
<tr>
<td>Cut-off Frequency</td>
<td>First-order low-pass filter cut-off frequency, in Hz</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the motor</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

The input signal \( \theta \) is the motor rotor electrical angle, in per unit. The output \( \omega_r \) is the estimated motor speed, in per unit. The output \( \text{rpm} \) is the estimated motor speed, in rpm. A first-order low-pass filter is used at the output variables.
5.5.2 Zero-Order Hold

A zero-order hold samples the input at the point of sampling. The output remains unchanged between two sampling points.

**Image:**

![Image of Zero-Order Hold](image)

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the zero-order hold, in Hz</td>
</tr>
</tbody>
</table>

Like all other discrete elements, the zero-order hold has a free-running timer which determines the moment of sampling. The sampling moment is synchronized with the origin of the simulation time. For example, if the zero-order hold has a sampling frequency of 1000 Hz, the input will be sampled at 0, 1 msec., 2 msec., 3 msec., and so on.

**Example:**

In the following circuit, the zero-order hold sampling frequency is 1000 Hz. The input and output waveforms are shown on the left.

![Example Circuit](image)

Note that in above circuit, a continuous-domain integrator is also connected to the input sine source. This makes it a mixed continuous-discrete circuit, and a simulation time step selected for the continuous circuit will be used. With this time step, the familiar staircase-like waveform can be observed at the zero-order hold output.

Without the integrator, the circuit becomes a discrete circuit. Since only the calculation at the discrete sampling points is needed, the simulation time step will be equal to the sampling period, and only the results at the sampling points are available. The waveforms, as shown below, appear continuous. In fact the waveforms are discrete, and the connection between two sampling points makes it look like continuous.

![Discrete Circuit](image)
5.5.3 z-Domain Transfer Function Block

A z-domain transfer function block is expressed in polynomial form as:

\[ H(z) = \frac{b_0 \cdot z^N + b_1 \cdot z^{N-1} + \ldots + b_{N-1} \cdot z + b_N}{a_0 \cdot z^N + a_1 \cdot z^{N-1} + \ldots + a_{N-1} \cdot z + a_N} \]

If \( a_0 = 1 \), the expression \( Y(z) = H(z) \cdot U(z) \) can be expressed in difference equation as:

\[ y(n) = b_0 \cdot u(n) + b_1 \cdot u(n-1) + \ldots + b_N \cdot u(n-N) - \]
\[ [a_1 \cdot y(n-1) + a_2 \cdot y(n-2) + \ldots + a_N \cdot y(n-N)] \]

### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Order ( N )</td>
<td>Order ( N ) of the transfer function</td>
</tr>
<tr>
<td>Coeff. ( b_0 ) ... ( b_N )</td>
<td>Coefficients of the numerator (from ( b_0 ) to ( b_N ))</td>
</tr>
<tr>
<td>Coeff. ( a_0 ) ... ( a_N )</td>
<td>Coefficients of the denominator (from ( a_0 ) to ( a_N ))</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

### Example:

The following is a second-order transfer function:

\[ H(z) = \frac{400.e^3}{z^2 + 1200 \cdot z + 400.e^3} \]

Assuming a sampling frequency of 3 kHz, the specification will be:

<table>
<thead>
<tr>
<th>Order ( N )</th>
<th>2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Coeff. ( b_0 ) ... ( b_N )</td>
<td>0. 0. 400.e3</td>
</tr>
<tr>
<td>Coeff. ( a_0 ) ... ( a_N )</td>
<td>1. 1200. 400.e3</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>3000.</td>
</tr>
</tbody>
</table>

5.5.3.1 Integrator

There are three types of integrators: regular integrator, external resettable integrator, and internal resettable integrator.

### Images:

<table>
<thead>
<tr>
<th>Regular Integrator</th>
<th>Internal Resettable Integrator</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Regular Integrator" /></td>
<td><img src="image2.png" alt="Internal Resettable Integrator" /></td>
</tr>
</tbody>
</table>
The output of an external resettable integrator can be reset by an external control signal (at the bottom of the block). With the edge reset (reset flag = 0), the integrator output is reset to zero at the rising edge of the control signal. With the level reset (reset flag = 1), the integrator output is reset to zero as long as the control signal is high (1).

The output of an internal resettable integrator is reset to 0 whenever the output reaches either the lower limit or the upper limit. The integrator works in the same way as the external resettable integrator with the edge reset, except that users do not need to set up the external reset circuit in this case.

If we define $u(t)$ as the input, $y(t)$ as the output, $T_s$ as the sampling period, and $H(z)$ as the discrete transfer function, the input-output relationship of an integrator can be expressed under different integration algorithms as follows.

With trapezoidal rule:

$$H(z) = \frac{T_s}{2} \cdot \frac{z+1}{z-1}$$

$$y(n) = y(n-1) + \frac{T_s}{2} \cdot (u(n) + u(n-1))$$

With backward Euler:

$$H(z) = T_s \cdot \frac{z}{z-1}$$

$$y(n) = y(n-1) + T_s \cdot u(n)$$

With forward Euler:

$$H(z) = T_s \cdot \frac{1}{z-1}$$

$$y(n) = y(n-1) + T_s \cdot u(n-1)$$

### 5.5.3.2 Differentiator

The transfer function of a discrete differentiator is:

$$H(z) = \frac{1}{T_s} \cdot \frac{z-1}{z}$$

where $T_s$ is the sampling period. The input-output relationship can be expressed in difference equation as:

$$y(n) = \frac{1}{T_s} \cdot (u(n) - u(n-1))$$
5.5.3.3 Digital PI Controller

A digital PI controller is defined below.

The transfer function of an analog PI controller in $s$-domain is defined as:

$$G(s) = k \cdot \frac{1 + \frac{sT}{sT}}{sT}$$

The digital PI controller is obtained by discretizing the analog PI controller using the backward Euler method. The implementation of the controller is shown below:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the PI controller</td>
</tr>
<tr>
<td>Time Constant</td>
<td>Time constant $T$ of the PI controller</td>
</tr>
<tr>
<td>Lower Output Limit</td>
<td>Lower limit $V_{\text{lower}}$ of the output</td>
</tr>
<tr>
<td>Upper Output Limit</td>
<td>Upper limit $V_{\text{upper}}$ of the output</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency $f_s$, in Hz</td>
</tr>
</tbody>
</table>

5.5.3.4 Digital PID Controller with Reset

The digital PID controller with reset is defined below. Depending on the setting of the gains, the block can be used as a PI or PD controller.

Image:
**Attribute:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
<tr>
<td>Proportional Gain</td>
<td>Proportional loop gain Kp</td>
</tr>
<tr>
<td>Integral Gain</td>
<td>Integral gain Ki</td>
</tr>
<tr>
<td>Derivative Gain</td>
<td>Derivative gain Kd</td>
</tr>
<tr>
<td>Upper Saturation</td>
<td>Maximum output limit, in per unit.</td>
</tr>
<tr>
<td>Lower Saturation</td>
<td>Minimum output limit, in per unit</td>
</tr>
</tbody>
</table>

In the image, the input with "r" is for the reset signal. The other input, please note, is the error between the reference and the feedback. The input Reset, when its value is greater than 0.5, clamps the integral output to zero. This function is useful to prevent the integrator from entering saturation before the feedback signal is available.

In the PID controller, the differential equation is transformed to the difference equation by means of the backward Euler approximation.

The block diagram of this conventional PID controller with anti-windup correction is shown below.

Let the sampling period be $T_s$, the integral gain and derivative gain are defined as:

$$K_i = \frac{T_s}{T_i}$$

$$K_d = \frac{T_d}{T_s}$$

**5.5.3.5 Digital Filters**

Four digital filter blocks are provided: 1st-order low-pass filter, 2nd-order low-pass filter, general digital filter, and general finite impulse response (FIR) filter. For both general filters, the filter coefficients can either be entered directly through the element property window, or be specified through a text file.
Attributes:

For 1st-order low-pass filter and 2nd-order low-pass filter:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the filter</td>
</tr>
<tr>
<td>Cut-off Frequency</td>
<td>Cut-off frequency $f_c$ ($f_c = \frac{\omega_c}{2\pi}$), in Hz</td>
</tr>
<tr>
<td>Damping Ratio</td>
<td>Damping ratio $\xi$ of the filter (for 2nd-order low-pass filter only)</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency $f_s$, in Hz</td>
</tr>
</tbody>
</table>

For General Digital Filter or FIR Filter that reads the coefficients directly:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Order $N$</td>
<td>Order $N$ of the transfer function</td>
</tr>
<tr>
<td>Coeff. $b_0...b_N$</td>
<td>Coefficients of the numerator (from $b_0$ to $b_N$)</td>
</tr>
<tr>
<td>Coeff. $a_0...a_N$</td>
<td>Coefficients of the denominator (from $a_0$ to $a_N$)</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency $f_s$, in Hz</td>
</tr>
</tbody>
</table>

For General Digital Filter or FIR Filter that reads the coefficients from a text file:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>File for Coefficients</td>
<td>Name of the file storing the filter coefficients</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency $f_s$, in Hz</td>
</tr>
</tbody>
</table>

The transfer functions of the low-pass filters are listed below.

For first-order low-pass analog filter in s-domain:

$$G(s) = k \cdot \frac{\omega_c}{s + \omega_c}$$

For second-order low-pass analog filter in s-domain:

$$G(s) = k \cdot \frac{\omega_c^2}{s^2 + 2\xi\omega_c s + \omega_c^2}$$

The 1st-order and 2nd-order digital filters are obtained by discretizing the analog filter using the Backward Euler method.

The transfer function of a general digital filter is expressed in polynomial form as:

$$H(z) = \frac{b_0 + b_1 \cdot z^{-1} + ... + b_{N-1} \cdot z^{-(N-1)} + b_N \cdot z^{-N}}{a_0 + a_1 \cdot z^{-1} + ... + a_{N-1} \cdot z^{-(N-1)} + a_N \cdot z^{-N}}$$

If $a_0 = 1$, the output $y$ and input $u$ can be expressed in difference equation form as:

$$y(n) = b_0 \cdot u(n) + b_1 \cdot u(n-1) + ... + b_N \cdot u(n-N) -$$

$$[a_1 \cdot y(n-1) + a_2 \cdot y(n-2) + ... + a_N \cdot y(n-N)]$$

If the denominator coefficients $a_0...a_N$ are not zero, this type of filter is called infinite impulse response (IIR) filter.

The transfer function of a FIR filter is expressed in polynomial form as:
If \( a_0 = 1 \), the output \( y \) and input \( u \) can be expressed in difference equation form as:

\[
y(n) = b_0 \cdot u(n) + b_1 \cdot u(n-1) + \ldots + b_N \cdot u(n-N)
\]

The coefficient file for block Digital Filter (file) and FIR Filter (file) has the following format:

For FIR Filter (file):

\[
\begin{align*}
N \\
b_0 \\
b_1 \\
\vdots \\
b_N
\end{align*}
\]

For Digital Filter (file), the format can be either one of the following:

\[
\begin{align*}
N & \quad \text{or} \quad N \\
b_0 & \quad b_0, a_0 \\
b_1 & \quad b_1, a_1 \\
\vdots & \quad \vdots \\
b_N & \quad b_N, a_N \\
a_0 & \\
a_1 \\
\vdots & \\
a_N
\end{align*}
\]

Example:

To design a 2nd-order low-pass Butterworth digital filter with the cut-off frequency \( f_c = 1 \text{ kHz} \), assuming the sampling frequency \( f_s = 10 \text{ kHz} \), using MATLAB, we have:

- Nyquist frequency \( f_n = f_s / 2 = 5 \text{ kHz} \)
- Normalized cut-off frequency \( f_c^* = f_c / f_n = 1/5 = 0.2 \)
- \([B, A] = \text{butter}(2, f_c^*)\)

which will give:

\[
B = [0.0201 \quad 0.0402 \quad 0.0201] = [b_0 \quad b_1 \quad b_2]
\]

\[
A = [1 \quad -1.561 \quad 0.6414] = [a_0 \quad a_1 \quad a_2]
\]

The transfer function is:

\[
H(z) = \frac{0.0201 + 0.0402 \cdot z^{-1} + 0.0201 \cdot z^{-2}}{1 - 1.561 \cdot z^{-1} + 0.6414 \cdot z^{-2}}
\]

The input-output difference equation is:

\[
y(n) = 0.0201 \cdot u(n) + 0.0402 \cdot u(n-1) + 1.561 \cdot y(n-1) - 0.6414 \cdot y(n-2)
\]

The parameter specification of the filter in PSIM will be:

| Order \( N \) | 2 |
If the coefficients are stored in a file, the file content will be:

<table>
<thead>
<tr>
<th>Coeff. $b_0...b_N$</th>
<th>0.0201 0.0402 0.0201</th>
</tr>
</thead>
<tbody>
<tr>
<td>Coeff. $a_0...a_N$</td>
<td>1. -1.561 0.6414</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>10000.</td>
</tr>
</tbody>
</table>

Or the file can also have the content as follows:

2
0.0201
0.0402
0.0201
1.
-1.561
0.6414

5.5.4 **Unit Delay**

A unit delay block provides one sampling period delay to the input.

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Initial Output Value</td>
<td>Initial value of the output of the block</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

The difference between the unit delay block and the time delay block is that the unit delay block is a discrete element and it delays the sampled points by one sampling period, whereas the time delay block is a continuous element and it delays the whole waveform by the delay time specified.

5.5.5 **Quantization Blocks**

Quantization blocks simulate the quantization process of an A/D converter. Two quantization blocks are provided: One with 1 LSB (least significant bit) quantization error, and the other with input offset with 0.5 LSB quantization error.

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>No. of Bits</td>
<td>Number of bits $N$</td>
</tr>
<tr>
<td>Vin_min</td>
<td>Lower limit of the input value $V_{in,min}$</td>
</tr>
</tbody>
</table>
To understand how the quantization blocks work, we will look at a special case where $N = 3$, $V_{in,min} = 0$, and $V_{in,max} = 1$. The input will be divided into $2^3$ (or 8) stages. Depending on the input level, the output will be one of the 3-bit discrete numbers 000, 001, 010, 011, 100, 101, 110, and 111. The output will have $2^3$ (or 8) levels, and $2^3 - 1$ (or 7) steps. If the binary number 000 corresponds to the decimal number 0, and the binary number 111 corresponds to the decimal number 0.875, and $V_{o,min} = 0$, and $V_{o,max} = 1$, we can plot the waveforms of the input, output, and the quantization error $V_{in} - V_o$ of the two quantization blocks as below.

The waveforms on the left are from the quantization block without the offset, and the waveforms on the right are from the quantization block with the offset.

As shown from the waveforms on the left, the quantization error of the quantization block is from 0 to 1 LSB (least significant bit), or $1/2^3$ (or 0.125).

For the quantization block with offset, a value of 0.5*LSB is added to the input before performing the quantization. This reduces the quantization error to -0.5 LSB to +0.5 LSB (except when the input is close to the maximum value), as shown from the waveforms on the right.

The figure below shows the input-output relationship of a general quantization block with offset.
The number of bits determines the quantization resolution. The input range, $V_{in,max} - V_{in,min}$, is divided into $2^N$ stages, with the width of each stage as:

$$
\Delta V_{in} = \frac{V_{in,max} - V_{in,min}}{2^N}
$$

except for the 1st stage where the width is $0.5 \Delta V_{in}$, and the last stage where the width is $1.5 \Delta V_{in}$. Note that for the quantization block without the offset, the width of the 1st and last stage is $\Delta V_{in}$.

If the input falls in the $k_{th}$ stage, the output will be calculated as:

$$
V_o = V_{o,min} + (k - 1) \cdot \Delta V_o
$$

where $k$ is from 1 to $2^N$, and the output step is calculated as:

$$
\Delta V_o = \frac{V_{o,max} - V_{o,min}}{2^N}
$$

Note that the value $V_{o,max}$ corresponds to the output value when the input is at $V_{in,max}$. But because of the quantization, the output can be represented in only $N$ levels, from 0 to $2^N-1$. As a result, the actual limit of the output is not $V_{o,max}$, but $V_{o,max} - \Delta V_o$, as shown in the figure above.

**Example:**

For a quantization block with the offset, let $N = 3$, $V_{in,min} = 0$, $V_{in,max} = 1$, $V_{o,min} = 0$, and $V_{o,min} = 1$. We have $\Delta V_{in} = \Delta V_o = 1/8$. If $V_{in} = 0.25$, it is in the 3rd stage ($k = 3$), and it corresponds to $V_o = 0 + (3 - 1) \cdot 1/8 = 0.25$. If $V_{in} = 0.6$, it is in the 6th stage ($k = 6$), and it corresponds to $V_o = 0 + (6 - 1) \cdot 1/8 = 0.625$.

### 5.5.6 Circular Buffers

A circular buffer is a memory location that can store an array of data. Two types of circular buffers are provided in PSIM: One with a single output, and the other with a vector output.
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Buffer Length</td>
<td>The length of the buffer</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

A circular buffer stores data in a buffer. When the pointer reaches the end of the buffer, it will start again from the beginning.

The circular buffer with single output is a type of first-in-first-out memory storage device, and the output is equal to the value being pushed out.

The output of the circular buffer with vector output is a vector array with the length equal to the buffer length. To access each memory location, use the memory read block.

Example:

If a circular buffer has a buffer length of 4 and a sampling frequency of 10 Hz, we have the buffer storage at different time as follows:

<table>
<thead>
<tr>
<th>Time</th>
<th>Input</th>
<th>Value at Memory Location</th>
<th>Output (for single-output buffer)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0.11</td>
<td>0.11</td>
<td>0</td>
</tr>
<tr>
<td>0.1</td>
<td>0.22</td>
<td>0.22</td>
<td>0</td>
</tr>
<tr>
<td>0.2</td>
<td>0.33</td>
<td>0.33</td>
<td>0</td>
</tr>
<tr>
<td>0.3</td>
<td>0.44</td>
<td>0.33</td>
<td>0.44</td>
</tr>
<tr>
<td>0.4</td>
<td>0.55</td>
<td>0.33</td>
<td>0.44</td>
</tr>
<tr>
<td>0.5</td>
<td>0.66</td>
<td>0.33</td>
<td>0.44</td>
</tr>
<tr>
<td>...</td>
<td>...</td>
<td>...</td>
<td>...</td>
</tr>
</tbody>
</table>

5.5.7 Convolution Block

A convolution block performs the convolution of two input vectors. The output is also a vector.

Image:

Let the two input vectors be:

\[ A = [a_m a_{m-1} a_{m-2} \ldots a_1] \]
\[ B = [b_n b_{n-1} b_{n-2} \ldots b_1] \]

We have the convolution of \( A \) and \( B \) as:

\[ C = A \otimes B = [c_{m+n-1} c_{m+n-2} \ldots c_1] \]

where

\[ c_i = \Sigma [a_{k+1} \cdot b_{j-k}], \quad k=0, \ldots, m+n-1; \quad j=0, \ldots, m+n-1; \quad i=1, \ldots, m+n-1 \]

Example:

If \( A = [1 \ 2 \ 3] \) and \( B = [4 \ 5] \), we have \( m = 3; \ n = 2; \) and the convolution of \( A \) and \( B \) is: \( C = [4 \ 13 \ 22 \ 15] \).
5.5.8 Memory Read Block

A memory read block is used to read the value of a memory location of a vector.

**Image:**

![Memory Read Block Image]

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Memory Index Offset</td>
<td>Offset from the starting memory location</td>
</tr>
</tbody>
</table>

A memory read block allows one to access the memory location of elements such as convolution block, vector array, and circular buffer. The index offset defines the offset from the starting memory location.

**Example:**

Let a vector be \( A = [2 \ 4 \ 6 \ 8] \). If index offset is 0, the memory read block output will be 2. If the index offset is 2, the output will be 6.

5.5.9 Data Array

This is a one-dimensional array. The output is a vector. The data are either entered directly (the element is called \( Array \) in the PSIM library) or specified in a file (the element is called \( Array (file) \) in the PSIM library).

**Image:**

![Data Array Image]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Array Length</td>
<td>The length of the data array ( N ) (for the element ( Array ) only)</td>
</tr>
<tr>
<td>Values</td>
<td>Values of the array (for the element ( Array ) only)</td>
</tr>
<tr>
<td>File for Coefficients</td>
<td>Name of the file storing the array (for the element ( Array (file) ) only)</td>
</tr>
</tbody>
</table>

If the array is read from a file, the file will have the following format:

\[
N \\
\ a_1 \\
... \\
\ a_N \\
\]

where \( N \) is the length of the array, and \( a_1, a_N \) are the array values.

**Example:**

To define an array \( A = [2 \ 4 \ 6 \ 8] \), we will have: Array Length = 4; Values = 2 4 6 8. If the array is to be read from a file, the file will be:

\[
4 \ 2 \ 4 \ 6 \ 8.
\]
5.5.10 Stack

A stack is a first-in-last-out register.

Image:

\[
\begin{array}{c}
\text{in} \\
push \\
pop \\
\text{out}
\end{array} \quad V_o
\]

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Stack Depth</td>
<td>The stack depth</td>
</tr>
</tbody>
</table>

The rising edge triggers the push or pop action. When a pop action is performed and the stack is empty, the output remains unchanged. When a push action is performed and the stack is already full, the data at the bottom of the stack will be pushed out and will be lost.

5.5.11 Motor Control Blocks

A list of function blocks are provided for motor control applications.

5.5.11.1 Ramp Control

This block implements the ramp up and ramp down function.

Image:

\[
\begin{array}{c}
\text{Ramp Output} \\
\text{Flag}
\end{array}
\]

Attribute:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Upper Limit</td>
<td>Maximum ramp output, in per unit</td>
</tr>
<tr>
<td>Lower Limit</td>
<td>Minimum ramp output, in per unit</td>
</tr>
<tr>
<td>Step Duration</td>
<td>Number of sampling periods (N) at each step. It must be an integer equal or greater than 1.</td>
</tr>
<tr>
<td>Step Size</td>
<td>The maximum ramp step change (V_{step}) at the output, in per unit</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency, in Hz</td>
</tr>
</tbody>
</table>

In the block image, the output node with a small dot is the ramp output, and the other output node is the flag indicating that the output equals the input.

If the input is greater than the output, the output will increment by \(V_{step}\) after a duration of \(N\) sampling periods.

If the input is less than output, the output will decrement by \(V_{step}\) after a duration of \(N\) sampling periods.

If the input is equal to the output, the flag will be set to 1. Otherwise it will be 0.
5.5.12 Multi-Rate Sampling System

A discrete system can have more than one sampling rate. The following system is used to illustrate this.

The system below has 3 sections. The first section has a sampling rate of 10 Hz. The output, Vo, fed back to the system and is sampled at 4 Hz in the second section. In the third section, the output is displayed at a sampling rate of 2 Hz.

It should be noted that a zero-order hold must be used between two elements with different sampling rates.

5.6 SimCoupler Module

The SimCoupler Module is an add-on module to the PSIM software. It provides interface between PSIM and Matlab/Simulink for co-simulation. With the SimCoupler Module, part of a system can be implemented and simulated in PSIM, and the rest of the system in Simulink. One can therefore make full use of PSIM’s capability in power simulation and Matlab/Simulink’s capability in control simulation in a complementary way.

The SimCoupler interface consists of two parts: the link nodes in PSIM, and the SimCoupler model block in Simulink. The images are shown below.

Images:

In PSIM, the In Link nodes receive values from Simulink, and the Out Link nodes send the values to Simulink. They are all control elements and can be used in the control circuit only. In Simulink, the SimCoupler model block is connected to the rest of the system through input/output ports.

5.6.1 Set-up in PSIM and Simulink

The use of the SimCoupler Module is easy and straightforward. As an example, the following shows a permanent-magnet synchronous motor (PMSM) drive system with the power stage implemented in PSIM, and the control in Simulink.
The following are the steps to set up SimCoupler for PSIM-Matlab/Simulink co-simulation for the example above.

**Adding the SimCoupler Block to the Simulink Library:**

Run the program "SetSimPath.exe" to add the SimCoupler block to the Simulink library and set up the SimCoupler Module for co-simulation of PSIM and Matlab/Simulink. After the execution, the SimCoupler block will appear as "S-function SimCoupler" in the Simulink Library Browser.

Note that this step is necessary, otherwise Simulink will not be able to find PSIM. With this, it is also not necessary to manually add the PSIM folder to the Matlab path.

Also, this program needs to be run only once. It needs to be run again only if the PSIM folder or Matlab folder has changed.

**In PSIM:**

- After the rest of the power circuit is created, connect three Out Link nodes to the low-pass filters of Phase A, B, and C currents, and rename them as “Ia”, “Ib”, and “Ic”; and connect one Out Link node to the speed sensor output and rename it as “Wrpm”.
- Connect three In Link nodes to the positive inputs of the comparators, and rename them as “Va”, “Vb”, and “Vc”.
- Go to the Simulate menu, and select Arrange SLINK Nodes. A dialog window will appear. Arrange the order of the In Link nodes (SLINK In) and Out Link nodes (SLINK Out) to be the same as how the input/output ports would appear in the SimCoupler model block in Simulink (the order of the ports is from the top to the bottom). In this example, the order will be “Va”, “Vb”, and “Vc” for the In Link nodes, and “Ia”, “Ib”, “Ic”, and “Wrpm” for the Out Link nodes.
- Save the schematic file. In this example, we assume that the file is saved to “C:\PSIM\pmsm_psim.sch”.

**In Simulink:**

- Start Matlab.
- Launch Simulink. Open an existing file or create a new file. After the rest of the system is created, go to the menu "S-function SimCoupler" in the Simulink Library Browser, select the SimCoupler block, and place it on the schematic.
- In the PMSM example file, double click on the SimCoupler block, and click on the Browser button to
locate and select the PSIM schematic file “C:\PSIM\pmsm_psim.sch”. Then click on Apply. The number of input and output ports of the SimCoupler model block will automatically match those defined in the PSIM netlist. In this case, there will be 3 input ports and 4 output ports.

- Go to the Simulation menu and select Simulation Parameters. Under Solver Options, set the Type to “Fixed-step”. Set Fixed step size to be the same as or close to PSIM’s time step. In this case, the time step is set to 0.1ms. More discussion on the selection of the solver option and the time step is given in the next section.

- The setup is now complete. Go to Simulink and start the simulation.

The SimCoupler Module supports Matlab/Simulink Release 13 and higher.

Please also note that when the SimCoupler model block is used in a feedback system in Simulink, the SimCoupler model block may be part of an algebraic loop (please refer to Matlab Help for more information on algebraic loops). Some versions of Matlab/Simulink can not solve a system containing algebraic loops, and other can solve the system but with degraded performance. To break an algebraic loop, place a memory block at each output of the SimCoupler model block. The memory block introduces one integration time step delay.

5.6.2 Solver Type and Time Step Selection in Simulink

There are certain restrictions on the selection of the solver type and the time step in Simulink when performing the co-simulation. To illustrate this, we use the following one-quadrant chopper circuit with average current mode control as an example.

The circuit on the left is all implemented and simulated in PSIM. The circuit on the right has the power stage implemented in PSIM, and the control implemented in Simulink. In both circuits, the PSIM time step is 2 us.

There are different ways of setting up Simulink to perform co-simulation. The recommend approach is to set the Solve Type to Fixed-step and define the Fixed step size to be the same or close to PSIM’s time step. The figure below shows this option.

It is recommended that Simulink use the same time step as PSIM, although we have found that, even if the Simulink time step is slightly larger than PSIM time step, satisfactory results are obtained. In this case, for
example, the time step is set to 20 us, 10 times larger than the PSIM time step.

If the Simulink Solver type is instead set to **Variable-step**, the simulation results will not be correct. The figure below shows this option.

![Diagram](image)

When the Simulink Solver type is set to **Variable-step**, in order to obtain correct results, a zero-order-hold must be placed at the input of the SimCoupler model block. Moreover, the zero-order-hold sample time must be the same or close to PSIM time step. The figure below shows the configuration.

![Diagram](image)

Therefore, Simulink must be set up to have the Solver Type as **Fixed-step** with the time step the same or close to the PSIM time step, or if the Solver Type is **Variable-step**, a zero-order-hold must be used with the sample time the same or close to PSIM time step.

### 5.6.3 Passing Parameters from Simulink to PSIM

One can set parameter values in Simulink, and pass them to PSIM. For example, to set the inductance of the inductor $L_1$ in Simulink, change the "Inductance" to $varL1$ in PSIM, as shown below.

![Inductor parameter](image)

In Simulink, double click on the SimCoupler block to open the property dialog, and click on **Add Variable**. Click on the newly added row in the list and type the variable name and value, as shown below.
The variable \textit{varL1} will now be accessible from PSIM.

5.7 \textbf{CosiMate Links}

CosiMate links provide the link between PSIM and CosiMate, a co-simulation platform that supports various software. Through the links, one can perform co-simulation between PSIM and the software that CosiMate supports. For more information on CosiMate, please visit www.chiastek.com.

The links consist of two parts: Input Port and Output Port. An input port represents a control signal input from CosiMate to PSIM, and an output port represents a control signal output from PSIM to CosiMate. During co-simulation, data are exchanged between PSIM and other software through these ports.

Note that the links will be functional only if one has CosiMate installed. For more details on how to set up the links, please refer to relevant CosiMate documents.

5.8 \textbf{Design Suite Blocks}

This section contains blocks that consist of basic power and control elements for specific motor drive system applications.

The following control blocks are provided:
- Torque Control (PMSM)
- Dynamic Torque Limit Control (PMSM)
- Voltage Control (PMSM)
- DC-DC Charging Control
- DC-DC Discharging Control
- DC-DC Regeneration Control

These blocks are part of the HEV Design Suite.
5.8.1 Torque Control (PMSM)

The Torque Control (PMSM) block is for linear PMSM machines only. It is defined as follow.

**Image:**

![Torque Control Block Diagram]

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ld (d-axis inductance)</td>
<td>d-axis inductance of the machine, in H</td>
</tr>
<tr>
<td>Lq (q-axis inductance)</td>
<td>q-axis inductance of the machine, in H</td>
</tr>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant of the machine, in V/krpm (mechanical speed)</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Integrator Gain</td>
<td>Gain of the torque loop integrator controller</td>
</tr>
<tr>
<td>Maximum Motor Torque</td>
<td>Maximum motor torque, in Nm</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>Base current value of the system, in A</td>
</tr>
<tr>
<td>Base Torque Value</td>
<td>Base torque value, in Nm</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the torque loop integrator controller, in Hz</td>
</tr>
</tbody>
</table>

The torque control block has the following inputs and outputs:

- **Id:** d-axis current feedback
- **Iq:** q-axis current feedback
- **Te:** Torque reference
- **Is:** Current amplitude reference
- **Tes:** Estimated torque developed by the motor

This block estimates the motor developed torque from the current feedback and motor parameters. A control loop based on a discrete integrator is used to regulate the motor torque and generate the motor current reference.

The block requires the parameters of the PMSM controlled and the inverter current rating.

5.8.2 Dynamic Torque Limit Control (PMSM)

The Dynamic Torque Limit Control (PMSM) block is for linear PMSM machines only.

**Image:**

![Dynamic Torque Limit Control Block Diagram]
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ld (d-axis inductance)</td>
<td>d-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Lq (q-axis inductance)</td>
<td>q-axis inductance of the PMSM machine, in H</td>
</tr>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant of the machine, in V/krpm (mechanical speed)</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Maximum Motor Torque</td>
<td>Maximum motor torque, in N*m</td>
</tr>
<tr>
<td>Maximum Motor Speed (rpm)</td>
<td>Maximum motor speed, in rpm</td>
</tr>
<tr>
<td>Maximum Motor Power</td>
<td>Maximum motor power, in W</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>Base voltage value of the system, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>Base current value of the system, in A</td>
</tr>
<tr>
<td>Base Mechanical Speed</td>
<td>Base mechanical speed, in rad/sec</td>
</tr>
<tr>
<td>Base Torque Value</td>
<td>Maximum inverter output voltage amplitude (phase peak), in V</td>
</tr>
</tbody>
</table>

The torque control block has the following inputs and outputs:

Id: d-axis current feedback
Iq: q-axis current feedback
Vdc: DC bus voltage feedback
Wm: Motor mechanical speed, in rad/sec.
Tcmd: Torque command
Te: Torque reference
nmb: Calculated speed limit of the maximum torque region, in rpm
FW: Flag of field weakening (1: in field weakening; 0: not in field weakening)

This block calculates the speed limit of the maximum torque region. When the motor speed is less than this speed limit, the motor operates in the maximum torque region. Otherwise, it operates in the maximum power region with field weakening control.

The block requires the parameters of the PMSM controlled and the inverter voltage rating.

5.8.3 Dynamic Torque Limit Control (Nonlinear PMSM)

The Dynamic Torque Limit Control (Nonlinear PMSM) block is for nonlinear PMSM machines only.

Image:
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Filter Cut-Off Frequency</td>
<td>Cut-off frequency fc of the internal low-pass filter, in Hz</td>
</tr>
<tr>
<td>Maximum Motor Torque</td>
<td>Maximum motor torque, in N*m</td>
</tr>
<tr>
<td>Maximum Motor Speed</td>
<td>Maximum motor speed, in rpm</td>
</tr>
<tr>
<td>Maximum Motor Power</td>
<td>Maximum motor power, in W</td>
</tr>
<tr>
<td>Base Voltage Value</td>
<td>Base voltage value of the system, in V</td>
</tr>
<tr>
<td>Base Current Value</td>
<td>Base current value of the system, in A</td>
</tr>
<tr>
<td>Base Mechanical Speed</td>
<td>Base mechanical speed, in rad/sec</td>
</tr>
<tr>
<td>Base Torque Value</td>
<td>Maximum inverter output voltage amplitude (phase peak), in V</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the internal low-pass filter, in Hz</td>
</tr>
</tbody>
</table>

The dynamic torque limit control block is for the control of nonlinear PMSM machines only. It has the following inputs and outputs, all in per unit value except Ld, Lq, and Lambda. When base values Vb, Ib, and Wmb are all 1, all input and output quantities are in real values.

Input Signals:
- Id: d-axis current feedback
- Iq: q-axis current feedback
- Ld: d-axis inductance Ld, in H
- Lq: q-axis inductance Lq, in H
- Lambda: Peak stator phase flux linkage, in Weber
- Vdc: DC bus voltage feedback
- Wm: Motor mechanical speed
- Tcmd: Torque reference input

Output Signals:
- Te: Torque reference output
- Wm_th: Calculated threshold speed of the constant torque region
- FW: Flag of field weakening (1: in field weakening; 0: not in field weakening)

This block calculates the threshold speed of the constant torque region. When the motor speed is less than this speed, the motor operates in the constant torque region. Otherwise, it operates in the constant power region with field weakening control.

A second-order low-pass digital filter, with a cut-off frequency of fc and a damping ratio of 0.7, is used to smooth out the change of the calculated threshold speed.

5.8.4 Voltage Control (PMSM)

The Voltage Control block is for linear PMSM machines only.

Image:
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vpk / krpm</td>
<td>Peak line-to-line back emf constant of the machine, in V/krpm (mechanical speed)</td>
</tr>
<tr>
<td>Number of Poles</td>
<td>Number of poles of the machine</td>
</tr>
<tr>
<td>Maximum Motor Torque</td>
<td>Maximum motor torque, in N*m</td>
</tr>
<tr>
<td>Number of Cells in Parallel</td>
<td>Number of cells Np in parallel in the battery pack</td>
</tr>
<tr>
<td>PI Gain</td>
<td>Gain of the voltage loop PI controller</td>
</tr>
<tr>
<td>PI Time Constant</td>
<td>Time constant of the voltage loop PI controller, in sec.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the voltage PI controller, in Hz</td>
</tr>
</tbody>
</table>

The voltage control block has the following inputs and outputs:

- Vdc*: DC bus voltage reference
- Vdc: DC bus voltage feedback
- Idc: DC bus current feedback
- Wm: Motor mechanical speed in rad/sec.
- Is: Current amplitude reference

This block uses a digital PI controller to regulate the dc bus voltage. Together with the dc bus current and the machine speed, it generates the machine current reference.

The block requires the parameters of the PMSM machine controlled.

5.8.5 DC-DC Charging Control

The DC-DC Charging Control block is defined as below.

Image:

![DC-DC Charging Control Diagram]

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Converter Rated Power</td>
<td>Rated power of the dc-dc converter, in W</td>
</tr>
<tr>
<td>Battery-side Rated Voltage</td>
<td>Converter rated voltage on the battery side, in V</td>
</tr>
<tr>
<td>Number of Cells in Series</td>
<td>Number of cells Ns in series in the battery pack</td>
</tr>
<tr>
<td>Number of Cells in Parallel</td>
<td>Number of cells Np in parallel in the battery pack</td>
</tr>
<tr>
<td>Voltage Derating Factor</td>
<td>Voltage derating factor Ks, from 0 (100% derating) to 1 (no derating)</td>
</tr>
<tr>
<td>Full Battery Voltage</td>
<td>Full (or maximum) voltage of the battery cell, in V</td>
</tr>
<tr>
<td>Battery Resistance</td>
<td>Internal resistance of the battery cell, in Ohm</td>
</tr>
<tr>
<td>Current PI Gain</td>
<td>Gain of the current loop PI controller</td>
</tr>
</tbody>
</table>
The dc-dc charging control block has the following inputs and outputs:

- **Vbatt**: Battery-side voltage
- **Ibatt**: Current flowing into the battery
- **Vm**: Modulation signal output

This block implements constant-voltage-constant-current charging control to a battery. When the battery terminal voltage is less than the battery float voltage (the float voltage is defined as the internal battery full voltage plus the voltage drop across the battery resistance), it is constant current charging, in which case the voltage is disabled and the current loop changes the battery at a constant current rate. The charging current amplitude is set to the converter rated current on the battery side.

On the other hand, when the battery terminal voltage reaches the float voltage, it is constant voltage charging. The voltage loop generates the reference for the current loop.

Digital PI controllers are used in the voltage and current loops.

### 5.8.6 DC-DC Discharging Control

The DC-DC Discharging Control block is defined as below.

**Image:**

![Discharging Control Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Current/Voltage Mode</td>
<td>Operation mode of the discharge control (0: current mode; 1: voltage mode)</td>
</tr>
<tr>
<td>Converter Rated Power</td>
<td>Rated power of the dc-dc converter, in W</td>
</tr>
<tr>
<td>Battery-side Rated Voltage</td>
<td>Converter rated voltage on the battery side, in V</td>
</tr>
<tr>
<td>DC Bus Voltage Reference</td>
<td>DC bus voltage reference, in V</td>
</tr>
<tr>
<td>Current PI Gain</td>
<td>Gain of the current loop PI controller</td>
</tr>
<tr>
<td>Current PI Time Constant</td>
<td>Time constant of the current loop PI controller, in sec.</td>
</tr>
<tr>
<td>Voltage PI Gain</td>
<td>Gain of the voltage loop PI controller</td>
</tr>
<tr>
<td>Voltage PI Time Constant</td>
<td>Time constant of the voltage loop PI controller, in sec.</td>
</tr>
<tr>
<td>Control Block Output Limit</td>
<td>The upper limit of the control block output Vm. The lower limit is 0.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the voltage and current PI controller, in Hz</td>
</tr>
</tbody>
</table>

The dc-dc discharging control block has the following inputs and outputs:

- **Vdc**: DC bus voltage feedback
Ibatt: Current flowing into the battery
Vm: Modulation signal output

This block implements constant-voltage or constant-current discharging control to a battery. When the operation mode is set to Voltage Mode (1), the converter regulates the dc bus voltage, and the voltage loop generates the reference for the current loop. When the operation mode is set to Current Mode (0), the converter regulates the current flowing into the dc bus to the maximum current that the converter can deliver.

Digital PI controllers are used in the voltage and current loops.

### 5.8.7 DC-DC Regeneration Control

The DC-DC Regeneration Control block is defined as below.

**Image:**

![Regeneration Control Diagram](image)

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Regen Power Threshold</td>
<td>Threshold of the motor power level. Beyond the threshold, regeneration is enabled.</td>
</tr>
<tr>
<td>Regen Enable Time</td>
<td>Time from which regeneration is enabled. Before this time, regeneration is disabled.</td>
</tr>
<tr>
<td>Sampling Frequency</td>
<td>Sampling frequency of the low-pass filter for speed feedback, in Hz</td>
</tr>
</tbody>
</table>

The dc-dc regeneration control block has the following inputs and outputs:

- **Vdc**: DC bus voltage feedback
- **Tes**: Estimated developed torque of the traction motor
- **Wm**: Mechanical speed of the traction motor in rad/sec.
- **Rgn**: Regeneration flag (0: no regeneration; 1: regeneration)

This block generates a regeneration flag based on the dc bus voltage and the traction motor power. When the motor power is negative (in generation mode) and the power amplitude exceeds the threshold, the regeneration flag is set to 1 to enable regeneration.

To avoid false triggering due to start-up transient, a regeneration enable time is defined. Regeneration is possible only after this time has passed.
This chapter provides descriptions for the components in PSIM element library’s Other section.

6.1 Switch Controllers

A switch controller has the same function as a switch gate/base drive circuit in an actual circuit. It receives the input from the control circuit, and controls switches in the power circuit. One switch controller can control multiple switches simultaneously.

6.1.1 On-Off Switch Controller

On-off switch controllers are used as the interface between control gating signals and power switches. The input, which is a logic signal (either 0 or 1) from the control circuit, is passed to the power circuit as the gating signal.

**Example:**

The circuit below implements the step change of a load. In the circuit, the on-off switch controller is used to control the bi-directional switch. The step voltage source, which is connected to the controller input, changes from 0 to 1 at the time of 12 ms. The closure of the switch results in the short-circuit of the resistor across the switch and the increase of the current.

6.1.2 Alpha Controller

An alpha controller is used for delay angle control of thyristor switches or bridges. There are three input for the controller: the alpha value, the synchronization signal, and the gating enable/disable signal. The transition of the synchronization signal from low to high (from 0 to 1) provides the synchronization and this corresponds to the moment when the delay angle alpha equals zero. A gating with a delay of alpha degrees is generated and sent to the thyristors. The alpha value is updated instantaneously.
The input for the delay angle $\alpha$ is in deg.

**Example:**

The figure below shows a thyristor circuit using delay angle control. In the circuit, the zero-crossing of $v_s$, which corresponds to the moment that the thyristor would start conducting naturally, is used to provide the synchronization. The delay angle is set at 30°. The gating signal is delayed from the rising edge of the synchronization signal by 30°.

### 6.1.3 PWM Lookup Table Controller

There are four input signals in a PWM lookup table controller: the modulation index, the delay angle, the synchronization signal, and the gating enable/disable signal. The gating pattern is selected based on the modulation index. The synchronization signal provides the synchronization to the gating pattern. The gating pattern is updated when the synchronization signal changes from low to high. The delay angle defines the relative angle between the gating pattern and the synchronization signal. For example, if the delay angle is 10 deg., the gating pattern will be leading the synchronization signal by 10 deg.
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>Switching frequency, in Hz</td>
</tr>
<tr>
<td>Update Angle</td>
<td>Update angle, in deg., based on which the gatings are internally updated. If the angle is 360°, the gatings are updated at every cycle. If it is 60°, the gatings are updated at every 60°.</td>
</tr>
<tr>
<td>File Name</td>
<td>Name of the file storing the PWM gating pattern</td>
</tr>
</tbody>
</table>

A lookup table, which is stored in a file, contains the gating patterns. It has the following format:

\[ n, m_1, m_2, \ldots, m_n, k_1, G_{1,1}, G_{1,2}, \ldots, G_{1,k_1}, k_2, G_{2,1}, G_{2,2}, \ldots, G_{2,k_2}, \ldots, k_n, G_{n,1}, G_{n,2}, \ldots, G_{n,k_n} \]

where \( n \) is the number of gating patterns; \( m_i \) is the modulation index correspondent to Pattern \( i \); and \( k_i \) is the number of switching points in Pattern \( i \). The modulation index array \( m_1 \) to \( m_n \) should be monotonically increasing. The output will select the \( i_{th} \) pattern if the input is smaller than or equal to \( m_i \). If the input exceeds \( m_n \), the last pattern will be selected.

The following table shows an example of a PWM pattern file with five modulation index levels and 14 switching points.

| Voltage/current sensors measure the voltages/currents of the power circuit and send them to the control circuit. The current sensor has an internal resistance of 1 \( \mu \Omega \). |

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Voltage Sensor</td>
<td></td>
</tr>
<tr>
<td>Current Sensor</td>
<td></td>
</tr>
</tbody>
</table>

6.2 Sensors

Voltage/current sensors measure the voltages/currents of the power circuit and send them to the control circuit. The current sensor has an internal resistance of 1 \( \mu \Omega \).
In the images, the dot indicates the positive terminal.

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain of the sensor</td>
</tr>
</tbody>
</table>

### 6.3 Probes, Meters, and Scopes

Probes and meters are used to measure voltages, currents, power, or other quantities, while scopes are used to display voltage and current waveforms.

#### 6.3.1 Probes and Meters

Below find the images of the ac ammeter, dc ammeter, voltage probe, current probe, ac voltmeter, dc voltmeter, single-phase and 3-phase wattmeters and kilowatt hour (kWh) meters, VAR meters, and VA-Power Factor meters. A voltage probe measures a node voltage with respect to ground. A two-terminal voltage probe measures the voltage between two nodes. A current probe or meter measures the current flowing into the meter from the dotted side. Similarly, a power meter measures the power flowing into the meter from the dotted side. Note that all the probes and meters, except the node-to-ground probe, are allowed in the power circuit only.

While voltage/current probes measure the instantaneous voltage or current, meters measure the dc or ac quantities. A small resistor of 1 μΩ is used in the current probe internally to measure the current.

**Images:**

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Operating Frequency</td>
<td>Operating frequency or fundamental frequency of the ac meter, in Hz</td>
</tr>
<tr>
<td>Cut-off Frequency</td>
<td>Cut-off frequency of the low-pass/high-pass filter, in Hz</td>
</tr>
<tr>
<td>kWh Meter Start Time</td>
<td>Time from which the kilowatt hour meter starts, in sec. (for W/kWh meters only)</td>
</tr>
<tr>
<td>kWh Meter Stop Time</td>
<td>Time at which the kilowatt hour meter stops, in sec. (for W/kWh meters only)</td>
</tr>
<tr>
<td>VA Display Flag</td>
<td>Display flag for apparent power (0: no display; 1: display) (for VA-Power Factor meters only)</td>
</tr>
<tr>
<td>PF Display Flag</td>
<td>Display flag for power factor (0: no display; 1: display) (for VA-Power Factor meters only)</td>
</tr>
<tr>
<td>DPF Display Flag</td>
<td>Display flag for displacement power factor (0: no display; 1: display) (for VA-Power Factor meters only)</td>
</tr>
</tbody>
</table>
In the images for the single-phase/3-phase wattmeter / kWh meter, the node with the letter "W" is for the real power output, in watt, and the node with the letter "kWh" is for the kilowatt hour output, in kilowatt-hour.

A low-pass filter is used in the dc meter and wattmeter models to filter out high-frequency components, whereas a high-pass filter is used in the ac meter models to filter out the dc component. The cut-off frequency determines the transient response of the filter.

Except the voltage and current probes, the readings of all the meters are meaningful only when the readings reach the steady state.

The single-phase and 3-phase VAR meter measure the reactive power (VAR) at the fundamental frequency; and the VA-Power Factor meters measure the apparent power (VA), the total power factor (PF), and the displacement power factor (DPF). The kilowatt hour meter reading gives the integration of the real power over a time interval defined by the start time and the stop time.

For a single-phase circuit, the real power $P$, reactive power $Q$, apparent power $S$, total power factor $PF$, and the displacement power factor $DPF$ are defined as follows.

Assume both the voltage and current contains harmonics, i.e.

$$v(t) = \sqrt{2} V_1 \sin(\omega_1 t + \phi_1) + \sqrt{2} V_2 \sin(\omega_2 t + \phi_2) + ...$$

$$i(t) = \sqrt{2} I_1 \sin(\omega_1 t + \theta_1) + \sqrt{2} I_2 \sin(\omega_2 t + \theta_2) + ...$$

where $\omega_1$ is the fundamental frequency and all others are harmonic frequencies. We have the rms values of the voltage and current as:

$$V_{rms} = \sqrt{V_1^2 + V_2^2 + ...}$$

$$I_{rms} = \sqrt{I_1^2 + I_2^2 + ...}$$

The real power (or average power) $P$ is defined as:

$$P = \frac{1}{T} \int_0^T (v(t) \cdot i(t)) dt$$

where $T$ is the fundamental period.

The reactive power $Q$ is defined as:

$$Q = V_1 \cdot I_1 \cdot \sin(\phi_1 - \theta_1)$$

Note that the reactive power is for the fundamental component only.

The apparent power $S$ is defined as:

$$S = V_{rms} \cdot I_{rms}$$

The total power factor $PF$ and the displacement power factor $DPF$ are then defined as follow:

$$PF = \frac{P}{S}$$

$$DPF = \cos(\phi_1 - \theta_1)$$

For the 3-phase circuit, the definitions are similar.

Note that all the 3-phase meters, including 3-phase wattmeter/kWh meter, VAR meter, VA-Power Factor meter, are for 3-phase 3-wire circuit only, and cannot be used in 3-phase 4-wire circuit. The models of the meters are based on the assumption that the summation of 3-phase voltages and currents must be equal to zero, that is:

$$v_a + v_b + v_c = 0$$

$$i_a + i_b + i_c = 0$$

For 3-phase 4-wire circuit, single-phase meters should be used instead.
To use the single-phase or 3-phase wattmeter/VAR meters, insert the meters into the circuit.

**Example:**

This example shows how single-phase and 3-phase meters are used. The circuit on the left shows the use of the wattmeter and VAR meter, and the circuit on the right shows the use of the three-phase wattmeter and VAR meter.

![Circuit Diagram](image)

### 6.3.2 Voltage/Current Scopes

While voltage/current probes and meters save the simulation results for post waveform processing, voltage/current scopes allow users to view simulation waveforms at runtime in the middle of the simulation.

Three scopes are provided: 1-channel voltage scope, 2-channel voltage scope, 4-channel voltage scope, and current scope.

Below are the images of the voltage and current scopes and their expanded view.

![Scope Images](image)

The 1-channel and 4-channel voltage scope and the current scope have the same interface. For the 4-channel scope, the channel can be selected through the drop-down channel selection, and the settings apply that the channel selected.

The scope is designed to operate in a similar way as the actual oscilloscope in the lab. It has 3 main sections: Timebase section, Channel section, and Trigger section.

In the Timebase section, the scale of time (x axis) is defined.

In the Channel section, the scale of the Y axis, as well as the offset and the color of the waveform, are defined. The channel display mode can be either DC, AC, or Gnd (for ground). When the display mode is in DC, the entire waveform is displayed. If the display mode is in AC, only the ac portion of the waveform is displayed.
When the display mode is *Gnd*, the waveform will show 0.

In the *Trigger* section, the trigger conditions are defined. The trigger can be set to either *ON* or *OFF*. When the trigger is off, the waveform is free-running, and the display of the waveform in the scope may vary from one frame to another. If the trigger is on, the waveform display will only start when the trigger conditions are met. This will lead to a steady waveform display.

There are three trigger modes: rising-edge triggering, falling-edge triggering, and one-shot triggering (if the *once* checkbox is checked, the one-shot triggering is selected). The one-shot triggering will trigger only once, and it is useful, for example, in situations where a transient needs to be captured.

The trigger level sets the level at which the triggering occurs. For example, if Channel A is selected with the rising-edge triggering and the trigger level of 0V, whenever the Channel A input crosses over 0 from negative to positive, triggering will occur and the waveform display will start from that instant.

On the scope, if the *Auto scale* checkbox is checked, the scale of all the channels will be automatically adjusted so that the waveforms are within the display of the scope.

Note that voltage scopes have connecting terminals which can be connected to either power circuit nodes or control circuit nodes. The scopes will display the node-to-ground voltages at these nodes.

The current scope, on the other hand, has no connecting terminals. It is associated with any element that has the parameter of the current flag, and it is enabled by right clicking on top of the element, and selecting the branch current under the *Current Scopes*, as shown below. After the branch current is selected, a check mark will appear in front of the branch current name.

If the element has multiple current flags, under the *Current Scopes* menu, there will be multiply branch currents, one corresponding to each current flag.

For example, for a 3-phase resistor R1, under the *Current Scopes* menu, there will be three branch currents: *I*(R1) A, *I*(R1) B, and *I*(R1) C. The letter "A", "B", and "C" refer to Channel A, B, and C, respectively. For example, if "*I*(R1) A", "*I*(R1) B", and "*I*(R1) C" are all selected, in the current scope, one can go to the *Channel* pull-down menu in the *Channel* section, and select one of the channels for display. If Channel A is selected, the scope will show the Phase A branch current *I*(R1).

### 6.4 Function Blocks

#### 6.4.1 Control-Power Interface Block

A control-to-power interface block passes a control circuit value to the power circuit. It is used as a buffer between the control and power circuit. The output of the interface block is treated as a voltage source when the power circuit is solved. With this block, some of the functions that can only be generated in the control circuit can be passed to the power circuit.

*Image:*
Example: A Constant-Power Load Model

In a constant-power dc load, the voltage $V$, current $I$, and power $P$ have the relationship as $P=V\times I$. Given the voltage and the power, the current can be calculated as $I=P/V$. This can be implemented using the circuit as shown below.

The load voltage is measured through a voltage sensor and is fed to a divider. The output of the divider gives the current value $I$. Since the voltage could be zero or a low value at the initial stage, a limiter is used to limit the current amplitude. This value is converted into the load current quantity through a voltage-controlled current source.

![Circuit Diagram](image1.png)

Example:

The following circuit illustrates how a control circuit signal can be passed to the power circuit. As seen from the power circuit, the CTOP block behaviors as a grounded voltage source.

![Circuit Diagram](image2.png)

6.4.2 Transformation Blocks

Function blocks of the following transformations are provided:
- abc-dqo transformation
- abc-αβ transformation
- αβ-dq transformation
- Cartesian-polar transformation

All these blocks can be used in either power circuit or control circuit.

6.4.2.1 abc-dqo Transformation

The abc-dqo function blocks perform the transformation between the abc coordinate and the dqo coordinate. The transformation is often referred to as the Park transformation.

Images:

![Transformation Diagrams](image3.png)
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Transformation Flag</td>
<td>Transformation flag (0: The q-axis leads the d-axis; 1: The q-axis lags the d-axis)</td>
</tr>
</tbody>
</table>

The angle $\theta$ at the bottom of the blocks is in rad.

It should be noted that, in power circuit, currents must first be converted into voltage quantities (using current-controlled voltage sources) before they can be transformed. Also, if an input terminal is not used (such as in the dqo-to-abc transformation block where only Phase d and q are not used, and Phase o is not used), it must be connected to ground.

Depending on the transformation flag, the transformation equations are as follows.

From abc to dqo, with the transformation flag set to 0:

$$
\begin{bmatrix}
  v_d \\
v_q \\
v_o
\end{bmatrix} = \frac{2}{3} \begin{bmatrix}
  \cos\theta & \cos\left(\theta - \frac{2\pi}{3}\right) & \cos\left(\theta + \frac{2\pi}{3}\right) \\
  -\sin\theta & -\sin\left(\theta - \frac{2\pi}{3}\right) & -\sin\left(\theta + \frac{2\pi}{3}\right) \\
  \frac{1}{2} & \frac{1}{2} & \frac{1}{2}
\end{bmatrix} \cdot 
\begin{bmatrix}
  v_a \\
v_b \\
v_c
\end{bmatrix}
$$

From abc to dqo, with the transformation flag set to 1:

$$
\begin{bmatrix}
  v_d \\
v_q \\
v_o
\end{bmatrix} = \frac{2}{3} \cdot 
\begin{bmatrix}
  \cos\theta & \cos\left(\theta - \frac{2\pi}{3}\right) & \cos\left(\theta + \frac{2\pi}{3}\right) \\
  \sin\theta & \sin\left(\theta - \frac{2\pi}{3}\right) & \sin\left(\theta + \frac{2\pi}{3}\right) \\
  \frac{1}{2} & \frac{1}{2} & \frac{1}{2}
\end{bmatrix} \cdot 
\begin{bmatrix}
  v_a \\
v_b \\
v_c
\end{bmatrix}
$$

Note that the coefficient $2/3$ in front of the transformation matrix means that the transformation is amplitude invariant, not power invariant. That is, the dq vector amplitude is equal to the peak amplitude of the three-phase sinusoidal waveforms. But the power in the dq frame must be multiplied by $3/2$ to have the same power, i.e. $Power = v_a * i_a + v_b * i_b + v_c * i_c = 3/2 * (v_d * i_d + v_q * i_q)$. To have the power invariant transformation, replace $2/3$ with $\sqrt{2}/3$, and 1/2 with $\sqrt{1/2}$.

From dqo to abc, with the transformation flag set to 0:

$$
\begin{bmatrix}
  v_a \\
v_b \\
v_c
\end{bmatrix} = 
\begin{bmatrix}
  \cos\theta & -\sin\theta & 1 \\
  \cos\left(\theta - \frac{2\pi}{3}\right) & -\sin\left(\theta - \frac{2\pi}{3}\right) & 1 \\
  \cos\left(\theta + \frac{2\pi}{3}\right) & -\sin\left(\theta + \frac{2\pi}{3}\right) & 1
\end{bmatrix} \cdot 
\begin{bmatrix}
  v_d \\
v_q \\
v_o
\end{bmatrix}
$$

From dqo to abc, with the transformation flag set to 1:

$$
\begin{bmatrix}
  v_a \\
v_b \\
v_c
\end{bmatrix} = 
\begin{bmatrix}
  \cos\theta & \sin\theta & 1 \\
  \cos\left(\theta - \frac{2\pi}{3}\right) & \sin\left(\theta - \frac{2\pi}{3}\right) & 1 \\
  \cos\left(\theta + \frac{2\pi}{3}\right) & \sin\left(\theta + \frac{2\pi}{3}\right) & 1
\end{bmatrix} \cdot 
\begin{bmatrix}
  v_d \\
v_q \\
v_o
\end{bmatrix}
$$
Example:
In this example, three symmetrical ac waveforms are transformed into dqo quantities. The angle $\theta$ is defined as $\theta = \omega t$ where $\omega = 2\pi*60$. Since the angle $\theta$ changes linearly with time, a piecewise linear voltage which has a ramp waveform is used to represent $\theta$. The simulation waveforms show the three-phase ac (top), the angle $\theta$ (middle), and the dqo output. In this example, the “q” component is constant, and both the “d” and the “o” components are zero.

6.4.2.2 abc-$\alpha\beta$ Transformation

The abc-$\alpha\beta$ function blocks perform the transformation between the abc coordinate and the $\alpha\beta$ coordinate. It is often referred to as the Clarke transformation.

Images:

<table>
<thead>
<tr>
<th>abc to $\alpha\beta$</th>
<th>ab to $\alpha\beta$</th>
<th>ac to $\alpha\beta$</th>
<th>$\alpha\beta$ to abc</th>
</tr>
</thead>
<tbody>
<tr>
<td>$a \rightarrow a$</td>
<td>$a \rightarrow a$</td>
<td>$a \rightarrow a$</td>
<td>$a \rightarrow a$</td>
</tr>
<tr>
<td>$b$</td>
<td>$b$</td>
<td>$b$</td>
<td>$b$</td>
</tr>
<tr>
<td>$c \rightarrow b$</td>
<td>$c \rightarrow b$</td>
<td>$c \rightarrow b$</td>
<td>$c \rightarrow b$</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

In the images, the letter "al" refers to $\alpha$, and the letter "be" refers to $\beta$. The transformation equations are:

From abc to $\alpha\beta$:

$$
\begin{bmatrix}
    v_a \\
    v_b \\
    v_c
\end{bmatrix}
= \frac{1}{\sqrt{3}}
\begin{bmatrix}
    1 & -1/2 & 1/2 \\
    0 & \sqrt{3}/2 & \sqrt{3}/2 \\
    \sqrt{3}/2 & 0 & \sqrt{3}/2
\end{bmatrix}
\begin{bmatrix}
    v_a \\
    v_b \\
    v_c
\end{bmatrix}
$$

From ab to $\alpha\beta$:

$$
\begin{bmatrix}
    v_a \\
    v_b
\end{bmatrix}
= \frac{1}{\sqrt{2}}
\begin{bmatrix}
    \sqrt{2}/2 & 0 \\
    \sqrt{2}/2 & \sqrt{2}/2
\end{bmatrix}
\begin{bmatrix}
    v_a \\
    v_b
\end{bmatrix}
$$

From ac to $\alpha\beta$:

$$
\begin{bmatrix}
    v_a \\
    v_b
\end{bmatrix}
= \frac{1}{\sqrt{2}}
\begin{bmatrix}
    \sqrt{2}/2 & 0 \\
    \sqrt{2}/2 & -\sqrt{2}/2
\end{bmatrix}
\begin{bmatrix}
    v_a \\
    v_b
\end{bmatrix}
$$

From $\alpha\beta$ to abc:
For the ab-to-\( \alpha \beta \) and ac-to-\( \alpha \beta \) transformation, it is assumed that \( v_a + v_b + v_c = 0 \).

### 6.4.2.3 \( \alpha \beta \)-dq Transformation

The \( \alpha \beta \)-dq function blocks perform the transformation from \( \alpha \beta \) to dq coordinate which is often referred as Park Transformation. The dq-\( \alpha \beta \) function blocks perform the transformation from dq to \( \alpha \beta \) coordinate which is often referred as Inverse Park Transformation.

**Images:**

<table>
<thead>
<tr>
<th>( \alpha \beta ) to dq (Park)</th>
<th>dq to ( \alpha \beta ) (Inverse Park)</th>
</tr>
</thead>
<tbody>
<tr>
<td>( \alpha ) ( \beta ) ( d )</td>
<td>( d ) ( \alpha ) ( \beta ) ( q )</td>
</tr>
<tr>
<td>( \beta ) ( q ) ( \theta )</td>
<td>( \theta ) ( \alpha ) ( \beta ) ( \sin ) ( \cos )</td>
</tr>
</tbody>
</table>

In the images, the letter "al" refers to \( \alpha \), and the letter "be" refers to \( \beta \). The phase angle input can be either \( \theta \) in radian or \( \sin(\theta) \) and \( \cos(\theta) \).

The transformation equations are:

**From \( \alpha \beta \) to dq:**

\[
\begin{bmatrix}
    v_d \\
v_q
\end{bmatrix} = \begin{bmatrix}
    \cos \theta & \sin \theta \\
    -\sin \theta & \cos \theta
\end{bmatrix} \cdot \begin{bmatrix}
    v_a \\
v_b
\end{bmatrix}
\]

**From dq to \( \alpha \beta \):**

\[
\begin{bmatrix}
    v_a \\
v_b
\end{bmatrix} = \begin{bmatrix}
    \cos \theta & -\sin \theta \\
    \sin \theta & \cos \theta
\end{bmatrix} \cdot \begin{bmatrix}
    v_d \\
v_q
\end{bmatrix}
\]

### 6.4.2.4 Cartesian-Polar Transformation

The Cartesian-polar function blocks perform the transformation between the Cartesian coordinate and the polar coordinate.

**Images:**

<table>
<thead>
<tr>
<th>Cartesian to polar</th>
<th>Polar to Cartesian</th>
</tr>
</thead>
<tbody>
<tr>
<td>( r ) ( \theta )</td>
<td>( r ) ( \theta )</td>
</tr>
<tr>
<td>( \theta ) ( r ) ( \theta )</td>
<td>( \theta ) ( r ) ( \theta )</td>
</tr>
</tbody>
</table>

In the images, the letter "r" refers to the amplitude, and "a" refers to the phase angle \( \theta \), in rad.

The transformation equations are:

**From Cartesian to polar:**

\[
\begin{bmatrix}
    r \\
    \theta
\end{bmatrix} = \begin{bmatrix}
    r \\
    \theta
\end{bmatrix}
\]
6.4.3 Math Function Blocks

The output of a math function block is expressed as the mathematical function of the inputs. With this block, one can implement complex and nonlinear relationship easily. Blocks with 1, 2, 3, 5, and 10 inputs are provided.

Images:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expression ( f(x_1, x_2, \ldots, x_n) )</td>
<td>Expression of the output versus inputs where ( n ) is the number of inputs</td>
</tr>
<tr>
<td>Expression ( df/dx_i )</td>
<td>Expression of the derivative of the function ( f ) versus the ( i )th input</td>
</tr>
</tbody>
</table>

The derivative \( df/dx_i \) can be set to zero.

The variables that are allowed in the expression are: \( T \) or \( t \) for time, and \( x_i \) (\( i \) from 1 to \( n \)) which represents the \( i \)th input. For example, for the 3-input math function block, the allowed variables are: \( T, t, x_1, x_2, \) and \( x_3 \). For the 1-input math function block, the variable \( x \), which refers to the only input, is also allowed.

6.4.4 Lookup Tables

There are four lookup table blocks: One-dimensional regular lookup table and lookup table with data from Simview graph, and 2-dimensional lookup tables with integer input and floating-point input.

All four lookup tables can be used in both power circuit and control circuit.

Images:
Attributes for one-dimensional lookup table (Simview graph):

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Graph File</td>
<td>Name of the Simview file to be used as the lookup table data</td>
</tr>
<tr>
<td>Input Column</td>
<td>Input column of the lookup table, selected from a drop-down menu after a graph file is loaded.</td>
</tr>
<tr>
<td>Output Column</td>
<td>Output column of the lookup table, selected from a drop-down menu after a graph file is loaded.</td>
</tr>
</tbody>
</table>

For 2-dimensional lookup tables, the node on the left is for the row index input, and the node on the top is for the column index input.

A one-dimensional lookup table has one input and one output. Two data arrays, corresponding to the input and output arrays, are stored in a lookup table.

A 2-dimensional lookup table with integer input has two inputs. The output data is stored in a 2-dimensional matrix. The two inputs correspond to the row and column indices of the matrix. For example, if the row index is 3 and the column index is 4, the output will be $A(3,4)$ where $A$ is the data matrix.

A 2-dimensional lookup table with floating-point input is similar to the lookup table with integer input. The difference is that inputs are floating-point values, and interpolation is used to calculate the output.

Except the one-dimensional lookup table (Simview graph) where data is defined in a Simview file, there are two ways to define lookup table data. One is to enter the data directly in the dialog window in the Lookup Table tab. Another is to prepare the lookup table externally using a text editor, and define the file in the dialog window.

To enter the data directly in the dialog window, define the number of rows (and columns for 2-dimensional lookup tables), and click on Set. Then enter the values in the data cells provided. For 2-dimensional lookup tables with floating-point input, also enter row input array in the left most column and column input array in the top most row.

To prepare the data externally in a text file, define the data in the format as described below. Then click on Open File... to load the file. Click on Reload Data if the text file is modified after it is loaded. Click on Save As... to save the data to an external file.

Note that the external text file is optional. When an external text file is not defined, the internal data is used. But if an external text file is defined, the text file takes the precedence and will overwrite the internal data. It is important to note that, if the dialog window is closed, the external file will be saved automatically when one closes the dialog window (by clicking on X at the upper right corner of the dialog window). Also, a copy of the external text file is saved into the schematic file. In the case where the schematic file is moved to a different computer and the external text file does not exist, PSIM will recreate the text file from the last time.

The data format for one-dimensional lookup tables is:
\[ V_{in}(1), V_{o}(1) \]
\[ V_{in}(2), V_{o}(2) \]
\[ \vdots \]
\[ V_{in}(N), V_{o}(N) \]

Data points can be separated by either comma or space, such as:
\[ V_{in}(1) \ V_{o}(1) \]
\[ V_{in}(2) \ V_{o}(2) \]
\[ \vdots \]
\[ V_{in}(N) \ V_{o}(N) \]

The input array $V_{in}$ must be monotonically increasing. Between two points, linear interpolation is used to obtain the output. When the value of the input is less than $V_{in}(1)$ or greater than $V_{in}(N)$, the output will be clamped to $V_{o}(1)$ or $V_{o}(N)$. 

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The data format for 2-dimensional lookup tables with integer input is:

\[ M, N \]
\[ A_{11}, A_{12}, \ldots, A_{1N} \]
\[ A_{21}, A_{22}, \ldots, A_{2N} \]
\[ \ldots \ldots \ldots \]
\[ A_{M1}, A_{M2}, \ldots, A_{MN} \]

where \( M \) and \( N \) are the number of rows and columns, respectively. Since the row or column index must be an integer, the input value is automatically converted to an integer. If either the row or column index is out of the range (for example, the row index is less than 1 or greater than \( M \)), the output will be zero.

The data format for 2-dimensional lookup tables with floating-point input is:

\[ M, N \]
\[ V_{r1}, V_{r2}, \ldots, V_{rM} \]
\[ V_{c1}, V_{c2}, \ldots, V_{cN} \]
\[ A_{11}, A_{12}, \ldots, A_{1N} \]
\[ A_{21}, A_{22}, \ldots, A_{2N} \]
\[ \ldots \ldots \ldots \]
\[ A_{M1}, A_{M2}, \ldots, A_{MN} \]

where \( m \) is the number of rows and \( n \) is the number of columns; \( V_r \) is the row vector and \( V_c \) is the column vector; and \( A(i,j) \) is the output value at Row \( i \) and Column \( j \). Note that Vectors \( V_r \) and \( V_c \) must be monotonically increasing.

If an input falls between two points, interpolation is used to calculate the value. If an input is less than the minimum or greater than the maximum value, the input will be limited to the minimum or maximum value.

**Examples:**

The following shows a one-dimensional lookup table:

1., 10.
2., 30.
3., 20.
4., 60.
5., 50.

If the input is 0.99, the output will be 10. If the input is 1.5, the output will be \[ 10 + \frac{(1.5 - 1) \cdot (30 - 10)}{2 - 1} = 20. \]

The following shows a 2-dimensional lookup table with integer inputs:

3, 4
1, -2, 4, 1.
2, 3, 5, 8.
3, 8, -2, 9.

If the row index is 2 and the column index is 4, the output will be 8. If the row index is 5, regardless of the column index, the output will be 0.

The following shows a 2-dimensional lookup table with floating-point inputs:

3, 4
1.1 2.2 3.3
1.2 2.3 3.4 4.5
1., -2., 4., 1.
2., 3., 5., 8.

If the row input is 2 and the column input is 3, the following table shows the four points that enclose the input point, and the output value of 3.826 through interpolation:
6.4.5 C Block

A C block allows users to enter C code directly without compiling the code, unlike in external DLL blocks where the code needs to be compiled into a DLL using an external compiler. The code of the C block will be interpreted and executed at runtime by a built-in C interpreter in PSIM.

The interface of the C block dialog window is shown below.

The number of input and output ports of the C block is defined in the *Number of Input/Output Ports* section. If the number of ports is changed, the image of the block in the schematic will change accordingly.

The function **Insert GetPsimValue** allows the C block to access element parameters and parameters defined in a parameter file. Assuming that the circuit has a resistor called R1, to access the resistance value of R1, click on **Insert GetPsimValue**. The following dialog window will appear.
Click on OK, and the following code will be inserted to the code:

```c
int nStatus = -1; // If the function succeeds, the value of nStatus will be 0.
double nValue = GetPsimValue(reserved_ThreadIndex, reserved_AppPtr, "R1", "Resistance", &nStatus);
```

The resistance of the resistor R1 will be obtained and placed in the variable `nValue`.

To access a variable, for example "alpha", defined in a parameter file, use the following code:

```c
int nStatus = -1;
double nValue = GetPsimValue(reserved_ThreadIndex, reserved_AppPtr, "", "alpha", &nStatus);
if(nStatus != 0)
{
    //optional error handling code
    printf("Error: alpha = %f, nStatus = %i \n", value, nStatus);
}
```

The value of the variable alpha will be obtained and placed in the variable `nValue`.

For faster simulation, the function GetPsimValue should be used in `SimulationBegin`, and the variable `nValue` should be defined as a global variable so that it can be accessed in the `SimulationStep` function.

The code area includes four main sections:

- **Variable/Function Definitions:** This section includes statements and global variable definition.
- **Simulation Step Function:** This function is called at each simulation step.
- **SimulationBegin Function:** This function is called only once at the beginning of simulation for initialization.
- **SimulationEnd Function:** This function is called only once at the end of simulation for termination.

Click on the **Check Code** button to check if the code has any compiling errors. Click on the **Edit Image** button to customize the image of the C block.

For example, assume that a C block has 2 inputs and 3 outputs. After numbers of input/output ports are defined, the C block will have an image in PSIM as follows:

```
+----+----+----+
| in0 |   | out0 |
+----+----+----+
      |   |     |
      |   |     |
      |   |     |
      | in1|   |
+----+----+----+
      |   |   |
      |   |   |
      |   |   |
      | out1|
+----+----+----+
      |   |   |
      |   |   |
      |   |   |
      | out2|
+----+----+----+
```

The node sequence is from the top to the bottom.

In C code, the `in` array is used to pass the values from PSIM into the C block, and the `out` array is used to pass the values from the C block back to PSIM. In this example, the first input, which corresponds to `in[0]` in the
code, is the node at the top left, and the first output, which corresponds to out[0] in the code, is at the top right. The difference between the C block and the external DLL block is that, even though the C block is easier to use, it does have the disadvantage that the custom code in the C block can not be debugged, while in the external DLL block it is possible to set break points and trace/step through the code for debugging.

6.4.6  Simplified C Block

A simplified C block is a special case of the C block. Unlike the C block that contains a variable/function definition section and three functions, the simplified C block contains only the C code that is called and ran at every time step, corresponding to the code for the SimulationStep function.

The interface of the simplified C block dialog window is shown below.

The number of input and output ports of the ports is defined in the Number of Input/Output Ports section. After the number of ports is changed, the image of the block in the schematic will change accordingly.

Variables that can be used in the code include:

- t: Time passed from PSIM
- delt: Time step passed from PSIM
- x1, x2, ... : Inputs 1, 2, etc.
- y1, y2, ... : Outputs 1, 2, etc.

When the checkbox "Enable Fixed Point Header Files" is checked, by clicking on Fixed Point Settings, one can define the fixed point data types of the C block inputs and outputs.

By clicking on the Variables button, one can define variables that can be passed from the main circuit into the C block. The variable can be a numerical value or a formula, for example:

- k1 = 15.2
- k1 = Freq/sqrt(2)

where Freq is a variable defined in a parameter file.

By clicking on the Insert GetPsimValue button, one can get the variables defined elsewhere and use them in the C code. The usage of this function is the same as in the C block.

Unlike the C block, the simplified C block can be used for automatic code generation.
6.4.7 External DLL Blocks

An external DLL (dynamic link library) block allows users to write code in C/C++, compile it into DLL using Microsoft Visual C/C++, and link it with PSIM. These blocks can be used in either the power circuit or the control circuit.

A DLL block receives values from PSIM as inputs, performs the calculation, and sends the results back to PSIM. PSIM calls the DLL routine at each simulation time step. However, when the inputs of the DLL block are connected to one of these discrete elements (zero-order hold, unit delay, discrete integrators and differentiators, z-domain transfer function blocks, and digital filters), the DLL block is called only at the discrete sampling times.

Two types of DLL blocks are provided: Simple DLL Block and General DLL Block. The simple DLL block has a fixed number of inputs and outputs, and the DLL file name is the only parameter that needs to be defined. On the other hand, the general DLL block allows users to define arbitrary number of inputs/outputs and additional parameters. Users can also customize the DLL block image.

The simple DLL block is easier to program and use.

Simple DLL blocks with 1 input/output up to 25 inputs/outputs are provided. The images and parameters of DLL blocks with 1, 3, and 6 inputs/outputs are shown below.

Images:

<table>
<thead>
<tr>
<th>1-input</th>
<th>3-input</th>
<th>6-input</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Image" /></td>
<td><img src="image2.png" alt="Image" /></td>
<td><img src="image3.png" alt="Image" /></td>
</tr>
</tbody>
</table>

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>File Name</td>
<td>Name of the DLL file</td>
</tr>
</tbody>
</table>

The node with a dot is for the first input (in[0]). The input/output node sequence is from the top to the bottom.

The images and parameters of a general DLL block are shown below.

Image (for a block with 2 inputs and 3 outputs):

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>DLL File</td>
<td>Name of the DLL file</td>
</tr>
<tr>
<td>Input Data File</td>
<td>Name of the input data file that DLL reads (optional)</td>
</tr>
<tr>
<td>Number of Input Nodes</td>
<td>Number of input nodes (optional)</td>
</tr>
<tr>
<td>Number of Output Nodes</td>
<td>Number of output nodes (optional)</td>
</tr>
<tr>
<td>IN Nodes</td>
<td>List of input nodes (optional)</td>
</tr>
</tbody>
</table>
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The node with a dot is the first input (in[0]). The input/output node sequence is from the top to the bottom.

By default, users define the number of inputs and outputs. But the number of inputs and outputs, the node names, as well as the number of parameters and the parameter names can all be defined inside the DLL routine. For more details on defining and programming for the general DLL block, please refer to the help file "Help General DLL Block.pdf" and related examples.

The name of the DLL file can be arbitrary. The DLL file can be placed in one of the two places, in the order of precedence: in the PSIM directory, and in the same directory as the schematic file that uses the DLL file.

**Note:** When a DLL file is used in multiple DLL blocks in a schematic, if global or static variables are declared and used in the DLL code, these global/static variables will be the same and be shared among all the DLL blocks. If this is not what users intended, the DLL calculation can be incorrect, and users should avoid using global/static variables in the code in this case.

Several examples using the simple DLL blocks and the general DLL blocks are provided in the "examples/custom DLL" sub-folder in the PSIM directory.

### 6.4.8 Embedded Software Block

An Embedded Software Block is a special type of the external DLL blocks. It is intended for modeling embedded software devices such as microcontrollers and DSP.

#### Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>DLL File</td>
<td>Name of the DLL file that defines the functionality and the interface of the block</td>
</tr>
<tr>
<td>Number of Nodes</td>
<td>Total number of input and output nodes</td>
</tr>
</tbody>
</table>

An Embedded Software Block has similar functionality as a general external DLL block. However, unlike the general DLL block whose connection nodes are predefined as either inputs or outputs, the Embedded Software Block allows the node types to be programmed as needed. Also, additional information, such as the exact instant at which the state of a variable changes, can be calculated and passed to and from PSIM.

The Embedded Software Block is a control circuit element, and can be used in the control circuit only.

For more information on how to use the Embedded Software Block, please refer to the document "Help Embedded Software Block.pdf".
6.5 IC Models

Several PWM IC and driver IC models are provided.

6.5.1 PWM IC

The following PWM IC models are provided:

Images:

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Model Level</td>
<td>All these IC models have two levels:</td>
<td>- Level 1: The PWM gating outputs are control signals with logic level of 1 (high) and 0 (low)</td>
</tr>
<tr>
<td></td>
<td>- Level 2: the PWM gating outputs are power signals which can directly drive three-state switches.</td>
<td></td>
</tr>
</tbody>
</table>

PWM IC Descriptions:

<table>
<thead>
<tr>
<th>Model</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>UC3823A/B, UC3825A/B</td>
<td>High speed PWM controller for high frequency switch-mode power supplies. The UC3823A and UC3823B and the UC3825A and UC3825B family of PWM controllers are improved versions of the standard UC3823 and UC3825 family.</td>
</tr>
<tr>
<td>UC3842/3843, UC3844/3845</td>
<td>Current mode fixed frequency PWM controller for off-line or dc-dc converters. The UC3842/3/4/5 family of control devices provides the necessary functions to implement off-line or dc-to-dc fixed frequency current mode control schemes.</td>
</tr>
<tr>
<td>UC3846</td>
<td>Current mode fixed frequency PWM controller for off-line or dc-dc converters. The UC3846 family of control ICs provides the necessary functions to implement fixed frequency, current mode control schemes.</td>
</tr>
<tr>
<td>UC3854, UC3854A/B</td>
<td>High power factor preregulator providing active power factor correction. UC3854A/B products are pin compatible enhanced versions of the UC3854. It provides all the functions necessary for active power factor corrected preregulators.</td>
</tr>
<tr>
<td>Driver IC Description:</td>
<td></td>
</tr>
<tr>
<td>------------------------</td>
<td>---</td>
</tr>
<tr>
<td><strong>UC3872</strong></td>
<td>Resonant lamp ballast controller. The UC3872 is a resonant lamp ballast controller optimized for driving cold cathode fluorescent, neon, and other gas discharge lamps.</td>
</tr>
<tr>
<td><strong>UCC3806</strong></td>
<td>Low power, dual output, current mode PWM controller. With the same block diagram and pinout of the popular UC3846 series, the UCC3806 line features increased switching frequency capability while reducing the bias current used within the device.</td>
</tr>
<tr>
<td><strong>UCC3817/3818</strong></td>
<td>BiCMOS power factor preregulator with average current mode control. The UCC3817/18 family provides all the functions necessary for active power factor corrected preregulators. The controller achieves near unity power factor by shaping the ac input line current waveform to correspond to that of the ac input line voltage.</td>
</tr>
<tr>
<td><strong>UCC3895</strong></td>
<td>BiCMOS advanced phase-shift PWM controller for full bridge power stage. The UCC3895 is a phase-shift PWM controller that implements control of a full-bridge power stage by phase shifting the switching of one half-bridge with respect to the other. It allows constant frequency pulse-width modulation in conjunction with resonant zero-voltage switching to provide high efficiency at high frequencies.</td>
</tr>
</tbody>
</table>

6.5.2 **Driver IC**

PSIM has implemented the following power switching devices’ driver models:

<table>
<thead>
<tr>
<th>Images:</th>
<th></th>
</tr>
</thead>
</table>

**Driver IC Description:**

<table>
<thead>
<tr>
<th>Driver IC</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>IR21834</strong></td>
<td>Half-bridge driver for high voltage, high speed power MOSFET and IGBT with dependent high and low side referenced output channels.</td>
</tr>
<tr>
<td><strong>IRS21867</strong></td>
<td>High and low side driver for voltage, high speed power MOSFET and IGBT driver with independent high and low side referenced output channels.</td>
</tr>
</tbody>
</table>
| **TC4423A, TC4424A, TC4425A** | 3A dual output high-speed power MOSFET drivers.  
TC4423A: dual inverting.  
TC4424A: dual non-inverting.  
TC4425A: one inverting and one non-inverting. |
| **TC4426A, TC4427A, TC4428A** | 1.5A dual output high-speed power MOSFET drivers.  
TC4426A: dual inverting.  
TC4427A: dual non-inverting.  
TC4428A: one inverting and one non-inverting. |
6.5.3 555 Timer

The 555 Timer is a highly stable device for generating accurate time delays or oscillation. Additional terminals are provided for triggering or resetting if desired. In the time delay mode of operation, the time is precisely controlled by external resistor and capacitor.

In PSIM model, the OUT signal of the 555 Timer is a control signal node.

6.6 Initial Values

The initial node voltages of the power circuit and control circuit can be defined using this block. This value will not be kept as soon as the simulation started.

6.7 Parameter File

A parameter file defines the variables used in a circuit. For example, the resistance of a resistor can be specified as R1, and R1 is defined in a parameter file. Also, a parameter file can be used by itself as a computational tool.

A parameter file is a text file created by a text editor. It supports the following format:

- // Text from the character // to the end of the line is treated as comment
- k1 = 12.3 // Define the value of the variable k1
- k1 = a + b*c // Define k1 in a math expression
- (global) k1 = 12.3 // Define k1 as a global variable (for use in SimCoder)
- L1 = 3m // power-of-ten suffix is supported. L1 = 3e-3
- C1 = 100uF // C1 = 100e-6. The unit "F" is ignored.

Note that, as compared to Version 9.1, the following format is no longer supported:

- LIMIT var1 Vlow Vupper // This should be replaced by the "if...else if..." statement
- % as comment. Now comments must start with double slash //. % is now used as modulo operation.
- var1 value (for example "R1 2.5"). Now an equal sign must be used to define a variable.
The definition "(global)" is used in SimCoder only for automatic code generation. Please refer to the SimCoder User Manual on how it is used. For PSIM simulation, this definition is ignored. That is, a parameter definition "(global) K1 = 1.2" is treated the same as "K1 = 1.2".

Conditional statements and error/warning message functions are supported, as shown below:

```c
if (k1 > 10)
{
    a = 10
    b = 1
}
else if (k1 <= 20)
{
    a = 20
    b = 2
}
else
{
    Error {"Error: The value of k1 is out of the range. k1 = %f", k1}
}
if (k1 == 20)
{
    Warning {"Warning: The value of k1 is equal to %.0f", k1}
}
```

When writing the conditional statements "if...else if...else...", the standard C syntax applies (without the semicolon ; at the end of each statement though).

In addition, the while loop is supported. For example,

```c
iflag = 1
a = 0
b = 0.1
while (iflag == 1)
{
    a = a + b
    if (a > 10)
        iflag = 0
}
```

Supported operators and mathematical functions in a parameter file are:

```
+       // addition
-       // subtraction
*       // multiplication
/       // division
%       // modulo operator that returns the remainder after division (e.g. 5 % 2 = 1)
^       // to the power of
=       // equal assignment
==      // conditional equal
!=      // not equal
>       // greater than
>=      // equal or greater than
<       // less than
<=      // equal or less than
!       // not
&&      // and
||      // or
sin(x)  // sine
cos(x)  // cosine
```
\[
\tan(x) \quad \text{// tangent}
\]
\[
\text{asin}(x) \quad \text{// arcsine}
\]
\[
\text{acos}(x) \quad \text{// arccosine}
\]
\[
\text{atan}(x) \quad \text{// arctangent}
\]
\[
\text{atan2}(y, x) \quad \text{// arctangent with x and y defined}
\]
\[
\sinh(x) \quad \text{// hyperbolic sine}
\]
\[
\cosh(x) \quad \text{// hyperbolic cosine}
\]
\[
\tanh(x) \quad \text{// hyperbolic tangent}
\]
\[
\text{pow}(x, y) \quad \text{// x to the power of y}
\]
\[
\text{sqrt}(x) \quad \text{// square root}
\]
\[
\text{exp}(x) \quad \text{// base-e exponential of x, i.e. e^x}
\]
\[
\ln(x) \text{ (or log}(x)\text{)} \quad \text{// natural logarithm of x (base e)}
\]
\[
\log_{10}(x) \quad \text{// common logarithm of x (base 10)}
\]
\[
\text{abs}(x) \quad \text{// absolute}
\]
\[
\text{sign}(x) \quad \text{// sign function that returns 1 if } x > 0, -1 \text{ if } x < 0, \text{ and 0 if } x = 0
\]
\[
\text{ceil}(x) \quad \text{// function that returns the integer larger than } x
\]
\[
\text{floor}(x) \quad \text{// function that returns the integer smaller than } x
\]
\[
\text{if } (...) \{ ... \} \text{ else } (...) \{ ... \} \text{ else } (...) \quad \text{// conditional if statement}
\]
\[
\text{iif} \text{ (condition, value1, value2)} \quad \text{// inline if statement (note it is "iif" not "if")}
\]
\[
\text{while } (...) \{ ... \} \quad \text{// while loop}
\]
\[
\text{Error } \{ \text{"Error text } %f, %f\text{”}, \text{var1, var2}\} \quad \text{// Error statement. Up to 5 variables are supported.}
\]
\[
\text{Warning } \{ \text{"Warning text } %f, %f\text{”}, \text{var1, var2}\} \quad \text{// Warning statement. Up to 5 variables are supported}
\]

Note that the input or output of all trigonometric functions is in rad. Also, the Error or Warning reporting functions can control the variable number format, as shown below.

\[
\text{Error } \{ \text{"Error message”}\}
\]
\[
\text{Error } \{ \text{"Error message } %.nf\text{”, k1}\} \quad \text{// Print the value of k1, where n is the number of digits after the }
\]
\[
\quad \text{// decimal point. For example, if k1 = 12.34, %.1f will give 12.3}
\]
\[
\text{Warning } \{ \text{"Warning message”}\}
\]
\[
\text{Warning } \{ \text{"Warning message } %.nf\text{”, k1}\} \quad \text{// Print the value of k1, where n is the number of digits after }
\]
\[
\quad \text{// the decimal point. For example, if k1 = 12.34, %.1f will give 12.3}
\]

An Error function will stop the simulation, while a Warning function will allow the simulation to proceed.

To display the variable values of a parameter file, go to \textbf{Edit >> Show Values}. For example, the figure below shows a parameter file on the left, and the values on the right.

The function \textbf{Show Values} provides a very convenient way of checking the calculation.

Parameter File in Circuit Schematic:

When a parameter file element is used in a circuit schematic, it has the same hierarchy as the circuit in which it resides. A variable defined in a parameter file in a higher-level circuit can be used in all lower circuits, but not the other way around. Also, a variable defined in a parameter file in circuit cannot be used in another circuit of the same level.
For example, assume that a main circuit contains a parameter file "main_param.txt", and the main circuit contains two subcircuits S1 and S2, with a parameter file "sub1_param.txt" in S1 and another parameter file "sub2_param.txt" in S2. A variable defined in "main_param.txt" can be used in both S1 and S2 circuits as well as in parameter files "sub1_param.txt" and "sub2_param.txt". However, a variable defined in "sub1_param.txt" or "sub2_param.txt" cannot be used in the higher level main circuit and in "main_param.txt".

Similarly, since Subcircuits S1 and S2 are parallel, a variable defined in "sub1_param.txt" cannot be used in Subcircuit S2 and "sub2_param.txt", and vice versa.

In addition, when PSIM saves a parameter file, it will save the information of both the relative path and absolute path of the parameter file, as well as a copy of the content of the parameter file.

When PSIM loads a schematic with a parameter file element, it will search and load the parameter file in the following order: relative path (relative to the schematic file), absolute path, and the local path (the local folder where the schematic file is). If PSIM still cannot find the parameter file, it will create the parameter file in the local schematic folder from the copy that it saved in the schematic file.

**Parameter Tool:**

With the capability to show variable values and handle conditional statements, the parameter file element becomes a very useful computational tool in its own right. To facilitate its usage, a function is provided to open a parameter file without the need of a schematic. To access this function, go to Utilities >> Parameter Tool.

### 6.8 AC Analysis

#### 6.8.1 AC Sweep

The frequency response of a circuit or a control loop can be obtained with the ac analysis. A key feature of the ac analysis in PSIM is that, a circuit can be in its original switchmode form, and no average model is required. Nevertheless, with the average model, it takes much shorter time to perform the ac analysis.

The following are the steps to set up the ac analysis:

- Identify a sinusoidal voltage source as the excitation source for the ac sweep.
- Place ac sweep probes at the desired output location. To measure the loop response of a closed control loop, use the node-to-node probe.
- Place the AC Sweep block on the schematic, and define the parameters of the ac sweep.
- Run the simulation.

Below are the images of the ac sweep probes and the AC Sweep block.

**Images:**

<table>
<thead>
<tr>
<th>AC Sweep Probe</th>
<th>AC Sweep Probe (loop)</th>
<th>AC Sweep</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="AC Sweep Probe" /></td>
<td><img src="image2.png" alt="AC Sweep Probe (loop)" /></td>
<td><img src="image3.png" alt="AC Sweep" /></td>
</tr>
</tbody>
</table>

**Attributes:**

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Start Frequency</td>
<td>Start frequency of the ac sweep, in Hz</td>
</tr>
<tr>
<td>End Frequency</td>
<td>End frequency of the ac sweep, in Hz</td>
</tr>
<tr>
<td>No. of Points</td>
<td>Number of data points</td>
</tr>
<tr>
<td>Flag for Points</td>
<td>Flag to define how the data points is generated.</td>
</tr>
<tr>
<td>Flag = 0: Points are distributed linearly in LOG10 scale</td>
<td></td>
</tr>
<tr>
<td>Flag = 1: Points are distributed linearly in linear scale</td>
<td></td>
</tr>
<tr>
<td>Source Name</td>
<td>Name of the excitation source</td>
</tr>
</tbody>
</table>
The principle of the ac analysis is that a small ac excitation signal is injected into the system as the perturbation, and the signal at the same frequency is extracted at the output. To obtain accurate ac analysis results, the excitation source amplitude must be set properly. The amplitude must be small enough so that the perturbation stays in the linear region. On the other hand, the excitation source amplitude must be large enough so that the output signal is not affected by numerical errors.

In general, a physical system has low attenuation in the low frequency range and high attenuation in the high frequency range. A good selection of the excitation source amplitude would be to have a relatively small amplitude at the low frequency, and a relatively large amplitude at the high frequency.

Sometimes, after ac analysis is complete, a warning message is displayed as follows:

**Warning:** The program did not reach the steady state after 60 cycles. See File “message.txt” for more details.

This message occurs when the software fails to detect the steady state at the ac sweep output after 60 cycles. To address this problem, one may increase damping in the circuit (by including parasitic resistances, for example), or adjust the excitation source amplitude, or reduce simulation time step. The file “message.txt” gives the information on the frequency at which this occurs and the relative error. The relative error will indicate how far the data point is from reaching the steady state.

**Example: Open-Loop Response of a Buck Converter**

The circuit on the left is an one-quadrant buck converter. An excitation source is injected to the modulation signal, and the output voltage is measured. The result of the ac analysis, on the right, shows the open-loop response of the output voltage versus the modulation signal.

**Example: Loop Transfer Function of a Closed-Loop Circuit**

The ac analysis can be used to find out the loop response of a closed-loop system. The circuit below shows a buck converter with average current mode control. By injecting the excitation signal into the current feedback path, and using the node-to-node ac sweep probe, we can obtain the loop transfer function directly. With the loop transfer function, one can determine the bandwidth of the control loop and the phase margin.

Please note that the ac sweep probe should be connected such that the dotted side is connected to the node after the excitation source injection.
Example: Loop Transfer Function of a Switchmode Power Supply

The loop transfer function of a switchmode power supply controlled by a PWM IC can also be determined in a similar way. The figure below shows a buck converter controlled by TI UC3842. The excitation source can be inserted in the feedback path, before the op. amp. output.

6.8.2 AC Sweep Multisine

The AC Sweep (multisine) block has the same functionality as the AC sweep. Its advantage is to simulate multiple frequency of sine-wave in only one cycle of the lowest frequency wave, resulting faster simulation.
Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Start Frequency</td>
<td>Start frequency of the ac sweep, in Hz</td>
</tr>
<tr>
<td>End Frequency</td>
<td>End frequency of the ac sweep, in Hz</td>
</tr>
<tr>
<td>No. of Points</td>
<td>Number of data points</td>
</tr>
<tr>
<td>Flag for Points</td>
<td>Flag to define how the data points is generated.</td>
</tr>
<tr>
<td>Source Name</td>
<td>Name of the excitation source</td>
</tr>
<tr>
<td>Source Amplitude</td>
<td>Excitation source peak amplitude at the start frequency.</td>
</tr>
<tr>
<td>Number of Cycles</td>
<td>The number of cycles of the excitation source amplitude to be simulated</td>
</tr>
<tr>
<td>Steady State Time</td>
<td>The time predicted when the circuit has completed transient and reached steady state, in second. User may make approximated estimation of this value or run a single time simulation to determine it.</td>
</tr>
</tbody>
</table>

6.9 Parameter Sweep

Parameter sweep can be performed on any parameters:

The image and parameters of the parameter sweep block are shown below.

Image:

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Name</td>
<td>Name of the parameter to be swept</td>
</tr>
<tr>
<td>Start</td>
<td>Starting value of the parameter</td>
</tr>
<tr>
<td>End</td>
<td>End value of the parameter</td>
</tr>
<tr>
<td>Increment</td>
<td>Increment step value of the parameter</td>
</tr>
<tr>
<td>Enabled</td>
<td>When checked, the parameter line will be enabled.</td>
</tr>
</tbody>
</table>

For example, let the resistance of a resistor be “Ro”. To sweep the resistance from 2 Ohm to 10 Ohm, with an increment step value of 2 Ohm, check the Enabled checkbox, and define the following:

<table>
<thead>
<tr>
<th>Name</th>
<th>Ro</th>
</tr>
</thead>
<tbody>
<tr>
<td>Start</td>
<td>2</td>
</tr>
<tr>
<td>End</td>
<td>10</td>
</tr>
<tr>
<td>Increment</td>
<td>2</td>
</tr>
</tbody>
</table>

Parameter sweep will produce two plots: One is the outputs versus time, and the other is the outputs at the last simulation point versus the swept parameter.

For example, a circuit has two outputs V1 and V2, and the resistance Ro is swept. The total simulation time is
0.1 sec. After the simulation, there will be two plots in Simview. One is V1 and V2 versus time. The other is V1 and V2 versus Ro. The V1 and V2 values used in the second plot are the values at the last simulation point at 0.1 sec.
Several types of independent voltage/current sources are available in PSIM. The notation of a current source direction is: the current flows out of the higher-potential node, through the external circuit, and back into the lower-potential node of the source.

Note that current sources can be used in the power circuit only.

### 7.1 Constant

The constant element allows users to define a constant. It behaves as a grounded voltage source.

**Image:**

```
[Constant Element Image]
```

**Attribute:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Value</td>
<td>Value of the constant</td>
</tr>
</tbody>
</table>

### 7.2 Time

The Time element is a special case of the piecewise linear voltage source. It is treated as a grounded voltage source, and the value is equal to the simulation time, in sec.

**Image:**

```
[Time Element Image]
```

### 7.3 Ground

There are three different ground elements in PSIM library. Although they are in different shape, they are electrically connected together. The different shape of these grounds provide the convenience for user to separate the grounding in different functional sections of the circuits.

**Images:**

<table>
<thead>
<tr>
<th>Description</th>
<th>Image</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ground</td>
<td>![Ground Image]</td>
</tr>
<tr>
<td>Ground (1)</td>
<td>![Ground (1) Image]</td>
</tr>
<tr>
<td>Ground (2)</td>
<td>![Ground (2) Image]</td>
</tr>
</tbody>
</table>
7.4 Voltage and Current Sources

7.4.1 DC Source

A dc source has a constant amplitude. The reference of the grounded dc voltage sources is the ground.

Images:

<table>
<thead>
<tr>
<th>DC</th>
<th>DC (battery)</th>
<th>Grounded DC (circle)</th>
<th>Grounded DC (T)</th>
<th>Current</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="DC Diagram" /></td>
<td><img src="image2.png" alt="DC (battery) Diagram" /></td>
<td><img src="image3.png" alt="Grounded DC (circle) Diagram" /></td>
<td><img src="image4.png" alt="Grounded DC (T) Diagram" /></td>
<td><img src="image5.png" alt="Current Diagram" /></td>
</tr>
</tbody>
</table>

Attribute:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Amplitude</td>
<td>Amplitude of the source</td>
</tr>
<tr>
<td>Series Resistance</td>
<td>Source series resistance, in Ohm (for DC and DC (battery) voltage sources only)</td>
</tr>
<tr>
<td>Series Inductance</td>
<td>Source series Inductance, in H (for DC and DC (battery) voltage sources only)</td>
</tr>
</tbody>
</table>

The series resistance and inductance represent the source impedance.

7.4.2 Sinusoidal Source

A sinusoidal source is defined as:

\[
v_o = V_m \cdot \sin(2\pi \cdot f \cdot t + \theta) + V_{offset}
\]

The specifications can be illustrated as follows.

Images:

<table>
<thead>
<tr>
<th>Voltage</th>
<th>Current</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image6.png" alt="Voltage Diagram" /></td>
<td><img src="image7.png" alt="Current Diagram" /></td>
</tr>
</tbody>
</table>

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Peak Amplitude</td>
<td>Peak amplitude $V_m$</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency $f$, in Hz</td>
</tr>
<tr>
<td>Phase Angle</td>
<td>Initial phase angle $\theta$, in deg.</td>
</tr>
<tr>
<td>DC Offset</td>
<td>DC offset $V_{offset}$</td>
</tr>
</tbody>
</table>
Series Resistance | Source series resistance, in Ohm (for voltage source only)
Series Inductance | Source series inductance, in H (for voltage source only)
Tstart | Starting time, in sec. Before this time, the source is 0.

To facilitate the setup of three-phase circuits, a symmetrical three-phase Y-connected sinusoidal voltage source is provided. The dotted phase of the source refers to Phase A.

### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>V (line-line rms)</td>
<td>Line-to-line rms voltage amplitude</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency $f$, in Hz</td>
</tr>
<tr>
<td>Initial Angle (phase A)</td>
<td>Initial angle for Phase A, in deg.</td>
</tr>
<tr>
<td>Series Resistance</td>
<td>Source series resistance, in Ohm</td>
</tr>
<tr>
<td>Series Inductance</td>
<td>Source series inductance, in H</td>
</tr>
</tbody>
</table>

#### 7.4.3 Square-Wave Source

A square-wave voltage source or current source is defined by peak-to-peak amplitude, frequency, duty-cycle, and DC offset. The duty cycle is defined as the ratio between the high-potential interval versus the period.

### Images:

#### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vpeak-peak</td>
<td>Peak-to-peak amplitude $V_{pp}$</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz</td>
</tr>
<tr>
<td>Duty Cycle</td>
<td>Duty cycle $D$ of the high-potential interval</td>
</tr>
<tr>
<td>DC Offset</td>
<td>DC offset $V_{offset}$</td>
</tr>
<tr>
<td>Phase Delay</td>
<td>Phase delay $\theta$ of the waveform, in deg.</td>
</tr>
</tbody>
</table>

The specifications of a square wave source are illustrated as follows.
When the phase delay $\theta$ is positive, the waveform is shifted to the right along the time axis.

### 7.4.4 Triangular/Sawtooth Sources

A triangular-wave voltage source or current source is defined by peak-to-peak amplitude, frequency, duty-cycle, and DC offset. The duty cycle is defined as the ratio between the rising-slope interval versus the period.

#### Images:

![Images](image)

#### Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vpeak-peak</td>
<td>Peak-to-peak amplitude $V_{pp}$</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz</td>
</tr>
<tr>
<td>Duty Cycle</td>
<td>Duty cycle $D$ of the rising slope interval</td>
</tr>
<tr>
<td>DC Offset</td>
<td>DC offset $V_{offset}$</td>
</tr>
<tr>
<td>Phase Delay</td>
<td>Phase delay $\theta$ of the waveform, in deg.</td>
</tr>
</tbody>
</table>

The specifications of a triangular wave source are illustrated as:

![Image](image)

When the phase delay $\theta$ is positive, the waveform is shifted to the right along the time axis.

A sawtooth-wave voltage source is a special case of the triangular source with the duty cycle of 1 and dc offset and phase delay of 0, and with one node grounded. It is defined as below:

#### Image:
7.4.5 Step Sources

A step voltage/current source changes from one level to another at a given time. Two types of step sources are provided: one that changes from 0 to a certain level (refer to as Step in the library), and the other that changes from one level to another level (referred to as Step (2-level) in the library).

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vpeak</td>
<td>Peak amplitude</td>
</tr>
<tr>
<td>Frequency</td>
<td>Frequency, in Hz</td>
</tr>
</tbody>
</table>

For the Step type source:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vstep</td>
<td>Value $V_{step}$ after the step change</td>
</tr>
<tr>
<td>Tstep</td>
<td>Time $T_{step}$ at which the step change occurs</td>
</tr>
</tbody>
</table>

For the Step (2-level) type source:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vstep1</td>
<td>Value $V_{step1}$ before the step change</td>
</tr>
<tr>
<td>Vstep2</td>
<td>Value $V_{step2}$ after the step change</td>
</tr>
<tr>
<td>Tstep</td>
<td>Time $T_{step}$ at which the step change occurs</td>
</tr>
<tr>
<td>T_transition</td>
<td>Transition time $T_{transition}$ from $V_{step1}$ to $V_{step2}$</td>
</tr>
</tbody>
</table>

The specifications of the voltage step sources are illustrated as follows:
7.4.6 **Piecewise Linear Source**

The waveform of a piecewise linear source consists of piecewise linear segments. It is defined by the number of points, the values and the corresponding time (in sec.). The values and times can be entered either separately, or in pair.

**Images:**

<table>
<thead>
<tr>
<th>Voltage</th>
<th>Current</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1.png" alt="Image" /></td>
<td><img src="image2.png" alt="Image" /></td>
</tr>
</tbody>
</table>

**Attributes:**

For the sources that define the values and times separately:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>Frequency of the waveform, in Hz</td>
</tr>
<tr>
<td>No. of Points n</td>
<td>No. of points</td>
</tr>
<tr>
<td>Values V1...Vn</td>
<td>Values at each point</td>
</tr>
<tr>
<td>Time T1...Tn</td>
<td>Time at each point, in sec.</td>
</tr>
</tbody>
</table>

For the sources that define the values and times in pair:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>Frequency of the waveform, in Hz</td>
</tr>
<tr>
<td>Times, Values (t1,v1) ...</td>
<td>Time and value at each point</td>
</tr>
</tbody>
</table>

The time and value pair must be enclosed by left and right brackets. The time and value can be separated by either a comma, such as (1.2m,5.5), or a space, such as (1.2m 5.5), or both, such as (1.2m, 5.5).

**Example:**

The following is a non-periodic piecewise linear source. It has 3 segments which can be defined by four points (marked in the figure).

![Image](image3.png)

The specification for the *piecewise linear* voltage source will be:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>0.</td>
</tr>
<tr>
<td>No. of Points n</td>
<td>4</td>
</tr>
<tr>
<td>Values V1...Vn</td>
<td>1. 1. 3. 3.</td>
</tr>
<tr>
<td>Time T1...Tn</td>
<td>0. 0.1 0.2 0.3</td>
</tr>
</tbody>
</table>

The specification for the *piecewise linear (in pair)* voltage source will be:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>Frequency</td>
<td>0.</td>
</tr>
<tr>
<td>Times, Values (t1,v1)...</td>
<td>(0., 1) (0.1, 1) (0.2, 3) (0.3, 3)</td>
</tr>
</tbody>
</table>
7.4.7 Random Source

The amplitude of a random voltage source (VRAND) or current source (IRAND) is determined randomly at each simulation time step. A random source is defined as:

\[ v_o = V_m \cdot n + V_{offset} \]

where \( V_m \) is the peak-to-peak amplitude of the source, \( n \) is a random number in the range of 0 to 1, and \( V_{offset} \) is the dc offset.

Images:

![Voltage and Current Symbols]

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Peak-Peak Amplitude</td>
<td>Peak-to-peak amplitude of the source</td>
</tr>
<tr>
<td>DC Offset</td>
<td>DC offset</td>
</tr>
</tbody>
</table>

7.4.8 Math Function Source

A math function source allows one to define the source in a mathematical expression.

Image:

![Math Function Symbol]

Attributes:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Expression</td>
<td>The mathematical expression of the source</td>
</tr>
<tr>
<td>Tstart</td>
<td>Start time of the source</td>
</tr>
</tbody>
</table>

In the expression, “T” or “t” represents time. For example, to implement a sinusoidal source, the expression will be: \( \sin(2\times3.14159\times60\times t + 2.09) \).

7.4.9 Voltage/Current-Controlled Sources

The following types of controlled sources are available:
- Voltage controlled voltage source
- Current controlled voltage source
- Voltage controlled current source
- Current controlled current source
- Variable-gain voltage controlled voltage source
- Variable-gain voltage controlled current source

The controlling current of a current controlled source must come from a RLC branch. Also, for a controlled current source, the controlling voltage or current can not be an independent source.

Note that controlled sources can be used in the power circuit only.
For voltage-controlled sources, the controlling voltage is from the positive node (+) to the negative node (-).

For current-controlled sources (with an arrow pointing from one node to another), the control nodes are connected across a RLC branch, and the direction of the controlling current is indicated by the arrow.

For current-controlled sources (with a wire connecting the two nodes), the controlling current flows from one control node to another, as indicated by the arrow. A 10-uOhm resistor is used to sense the controlling current.

The output of a controlled source, except variable-gain controlled sources, is equal to the gain multiplied by the controlling voltage or current. For the variable-gain controlled sources, the output is equal to the following:

\[ v_o = k \cdot v_{in2} \cdot v_{in1} \]
\[ i_o = k \cdot v_{in2} \cdot v_{in1} \]

Input 1 is on the side with the multiplication sign, and Input 2 is on the side with the letter \( k \).

The difference between a variable-gain controlled source and a nonlinear source with multiplication is that, for the nonlinear source with multiplication, values of both \( v_{in1} \) and \( v_{in2} \) at the current time step are used to calculate the output and are updated in each iteration. But for the variable-gain controlled source, it is assumed that the change of \( v_{in2} \) is small from one time step to the next, and the value of \( v_{in2} \) at the previous time step is used at the current time step. This assumption is valid as long as \( v_{in2} \) changes at a much slower rate as compared to \( v_{in1} \) and the time step is small as compared to the change of \( v_{in2} \). Variable-gain controlled sources can be used in circuits which may otherwise have convergence problem with nonlinear sources with multiplication.

**Example:**

The circuits below illustrates the use of current controlled voltage sources. In the circuit on the left, the voltage source is controlled by the inductor current \( i_s \). With a gain of 1, the waveform of the voltage \( V_s \) is equal to that of \( i_s \). In this way, a current quantity can be converted to a voltage quantity. These two circuits are equivalent.
7.4.10 Nonlinear Voltage-Controlled Sources

The output of a nonlinear voltage-controlled source is either the multiplication, division, or square-root of the inputs. They are defined as:

Nonlinear (multiplication): Output $v_o = k \cdot v_{in1} \cdot v_{in2}$ or $i_o = k \cdot v_{in1} \cdot v_{in2}$

Nonlinear (division): Output $v_o = k \cdot \frac{v_{in1}}{v_{in2}}$ or $i_o = k \cdot \frac{v_{in1}}{v_{in2}}$

Nonlinear (square-root): Output $v_o = k \cdot \sqrt{v_{in1}}$ or $i_o = k \cdot \sqrt{v_{in1}}$

Nonlinear (power): Output $v_o = \text{sign}(v_{in}) \cdot k \cdot (|v_{in}|)^{k_2}$

In the nonlinear power source, the term $\text{sign}(v_{in})$ is 1 if $v_{in}$ is positive, and it is -1 if $v_{in}$ is negative.

Note that these nonlinear sources can be used in the power circuit only.

Images:

<table>
<thead>
<tr>
<th>Multiplication</th>
<th>Division</th>
<th>Square-root</th>
<th>Power</th>
</tr>
</thead>
<tbody>
<tr>
<td><img src="image1" alt="Multiplication Diagram" /></td>
<td><img src="image2" alt="Division Diagram" /></td>
<td><img src="image3" alt="Square-root Diagram" /></td>
<td><img src="image4" alt="Power Diagram" /></td>
</tr>
</tbody>
</table>

Attributes:

For all the sources except the nonlinear power source:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the source</td>
</tr>
</tbody>
</table>

For the nonlinear power source:

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Gain</td>
<td>Gain $k$ of the source</td>
</tr>
<tr>
<td>Coefficient $k_1$</td>
<td>Coefficient $k_1$</td>
</tr>
<tr>
<td>Coefficient $k_2$</td>
<td>Coefficient $k_2$</td>
</tr>
</tbody>
</table>

For the nonlinear (division) source, Input 1 is on the side of the division sign.
8 Error/Warning Messages and Other Simulation Issues

8.1 Simulation Issues

8.1.1 Time Step Selection

PSIM uses the fixed time step in the simulation. In order to assure accurate results, the simulation time step should be properly chosen. The factors that limit the time step in a circuit include the switching period, widths of pulses or square waveforms, and intervals of fast transients. It is recommended that the time step should be at least one magnitude smaller than the smallest of the above.

8.1.2 Propagation Delays in Logic Circuits

The logic elements in PSIM are ideal, i.e. there is no propagation delay. If a logic circuit uses the propagation delays for its operation, a function block in PSIM, called the Time Delay block, needs to be added to represent the effect of the propagation delay.

To illustrate this, take a two-bit counter circuit as an example.

In the circuit on the left, the initial values of both Q₀ and Q₁ are assumed to be zero. At the clock rising edge, Q₀ will change to 1. Without delay, the position of Q₁, which should remain at 0, will toggle to 1 at the same time.

To prevent this, a time delay element with the delay period of one time step needs to be inserted between Q₀ and the input (J) of the second flip-flop.

8.1.3 Interface Between Power and Control Circuits

In PSIM, power circuits are represented in the discrete circuit form, and control circuits are represented in function block diagram. Power circuit components, such as RLC branches, switches, transformers, mutual inductors, current sources, floating voltage sources, and all types of controlled sources are not allowed in the control circuit. Similarly, control circuit components, such as logic gates, PI controllers, lookup tables, and other function blocks, are not allowed in the power circuit.

If there is a direct connection between the power circuit and the input of a control circuit element, a voltage sensor will be automatically inserted by the program. Similarly, if there is a direct connection between the output of a control circuit element and the power circuit, a control-power interface block will be automatically inserted. This is illustrated in the examples below.
8.1.4 FFT Analysis

When using FFT for the harmonic analysis, one should make sure that the following requirements are satisfied:
- The waveforms have reached the steady state;
- The length of the data selected for FFT should be the multiple integer of the fundamental period.

For a 60-Hz waveform, for example, the data length should be restricted to 16.67 msec. (or multiples of 16.67 msec.). Otherwise, the FFT results will be incorrect. The data is selected by clicking on X Axis in SIMVIEW, de-selecting Auto-scale in Range, and specifying the starting time and the final time. The FFT analysis is only performed on the data that are displayed on the screen.

Note that the FFT results are discrete. The FFT results are determined by the time interval between two consecutive data points, Δt, and the data length T_{length}. The data point interval Δt is equal to the simulation time step multiplied by the print step. In the FFT results, the frequency incremental step will be 1/T_{length}, and the maximum frequency will be 1/(2*Δt).

For example, if you take the FFT of a 1-kHz square waveform with a data length of 1 ms and a data point interval of 10 us, that is, T_{length} = 1 ms, and Δt = 10 us, the frequency incremental step will be: Δf = 1/T_{length} = 1 kHz. The maximum frequency will be: f_{max} = 1/(2*Δt) = 50 kHz.

8.2 Debugging

Some of the approaches in debugging a circuit is discussed in the following.

**Symptom:**
Simulation results show sudden changes (discontinuity) of inductor currents and capacitor voltages.

**Solution:**
This may be caused by the interruption of inductor current path and short-circuit of capacitor (or capacitor-voltage source) loops. Check the switch gating signals. If necessary, include overlap or dead time pulses to avoid open-circuit or shooting-through.
If an initial current is assigned to an inductor, initial switch positions should be set such that a path is provided for the current flow. Otherwise, the inductor current will be forced to start from zero.

**Symptom:**
Simulation waveforms look incorrect or inaccurate, or the waveform resolution is poor.

**Solution:**
This may be caused by two reasons. One is the time step. Since PSIM uses the fixed time step during
the entire simulation, one should make sure that the time step is sufficiently small. As a rule of thumb, the time step should be several tens times smaller than the switching period. Another reason is the problem of waveform display. One should make sure that the print step is not too big. To display all the data points, set the print step to 1.

8.3 Error/Warning Messages

The error and warning messages are listed in the following.

E-1 Input format errors occurred in the simulation.
It may be caused by one of the following:
• Incorrect/Incomplete specifications
• Wrong input for integers and character strings
Make sure that the PSIM library is not modified, and the PSIM simulator is up-to-date.
In the circuit file, character strings should be included between two apostrophes (like ‘test’). Also, make sure an integer is specified for an integer variable. The specification of a real number (like 3. instead of 3) for an integer will trigger the error message.

E-2 Error message: The node of an element is floating.
This can also be caused by a poor connection in PSIM. When drawing a wire between two nodes, make sure that the wire is connected to the terminal of the element.

W-1 Warning!!! The program failed to converge after 10 iterations when determining switch positions. The computation continues with the following switch positions: ... ...
This warning occurs when the program fails to converge when determining switching positions. Since the computation continues based on the switch positions at the end of the 10th iteration, results could be inaccurate. One should be cautious when analyzing the results.
There are many factors that cause this problem. The following measures can be taken to isolate and solve the problem:
- Check the circuit and make sure the circuit is correct.
- Check the switch gating signals.
- Connect small resistors/inductors in series with switches and voltage sources.

W-2 Warning!!! The program did not reach the steady state after 60 cycles when performing the ac sweep.
This warning occurs when the program fails to reach the steady state after 60 cycles when performing the ac sweep. The cause of the problem could be that the system is poorly damped at that particular frequency or the signal amplitude is too small.
You may try the following to isolate and solve the problem:
- Run the time-domain simulation with the excitation source at that frequency and see if time-domain waveforms are oscillatory.
- Increase the excitation voltage amplitude for larger signal level, or
- Reduce the time step for better accuracy and resolution.
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