

GODYS-PC: a Software Package for Modeling, Simulating and Analyzing Dynamic Systems

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Abstract—In this paper, we introduce GODYS-PC software package for modeling, simulating and analyzing dynamic systems. To illustrate the use of GODYS-PC we present a few examples which concern modeling and simulating of engineering systems. In order to compare GODYS-PC with widely used in academia and industry Simulink®, the same examples are provided both in GODYS-PC and Simulink®.

Keywords—Modeling, simulating and analyzing dynamic systems.

I. INTRODUCTION

THE purpose of this paper is to present GODYS-PC software package for modeling, simulating and analyzing dynamic systems. Typical areas in which GODYS-PC may be successfully applied come from a wide diversity of realistic situations in engineering, control system design, economics, biology and so on.

There are a number of continuous simulation languages currently in use in applied science and engineering, for example Simulink®, which is widely used in academia and industry. Simulink® provides a graphical user interface (GUI) for building models as block diagrams, using click-and-drag mouse operations ([1]). This is far from describing models by mathematical expressions like in GODYS-PC. A description and comparison of some of the most popular continuous simulation languages has been presented, for example, in [2]. A discussion on evolution of continuous modeling and simulation has been presented, for example, in [3].

II. SIMULATION OF DYNAMIC SYSTEMS USING GODYS-PC

The basic structure of GODYS-PC follows the CSSL standard presented in [4]. GODYS-PC (abbreviated from Graph Oriented Dynamic System Simulation for Personal Computers) is a new version of GODYS continuous simulation language. GODYS was originally developed at the Institute of Computer Science, Jagiellonian University, Kraków in the mid-1970s and has been implemented on Honeywell, ICL 1900 and IBM 360 computers respectively ([5], [6], [7], [8], [9]). It has been developed in recent years and has been implemented on Personal Computers.

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Using the same basic approach as GODYS, GODYS-PC provides an interactive simulation facility and a number of advanced features. One of these features is parameter optimization. In the case of parameter optimization a finite number of parameters has to be determined such that a cost function of these parameters is minimal ([10]). GODYS-PC provides four algorithms for parameter optimization in a cost functions. At most eight parameters may be optimized in a cost function in GODYS-PC.

GODYS-PC provides a set of standard functions like, for example, INTEG (integration function), DERIVT (derivation function), STEP (step input function) and so on. GODYS-PC provides over fifty standard functions. The user can define his own functions (in FORTRAN).

GODYS-PC statements may be placed anywhere on the line. Any source model or runtime commands may be continued onto another line by ending the first line with the symbol @. All text after the symbol # to the end of the line is considered as a comment. Equations describing a model may be written in any order. This is because GODYS-PC provides an algorithm for automatic sorting of equations of a model. The sorting algorithm is based on the theory of functional graphs ([7], [8]).

After describing a model one can simulate it, using a choice of integration method. GODYS-PC provides five fixed step integration methods and a one variable step integration method. GODYS-PC provides a set of statements for generating a graphic representation of calculated results.

A model described in GODYS-PC consists of the following two parts: a model description and a runtime commands. The model description defines a model of a system being modeled. The model description must be written in a file whose name ends in *.mod*. The runtime commands exercise this model (for example, they change parameters, execute runs, specify plots and so on). Runtime commands may be entered interactively or in a batch process. In the case of a batch process the runtime commands must be written in a file whose name ends in *.sim*. Runtime commands are read, decoded and executed in sequence.

GODYS-PC is written in FORTRAN and consists of two modules. One of them is a syntax-directed translator, which generates an object program in a language of an abstract machine. This machine is implemented by an effective interpreter, which is the main part of the second module ([9]).

In order to illustrate the use of GODYS-PC let us consider the following classical model of the spring-mass-damper system shown in Fig. 1, where M is the mass, F is the force, K is the spring constant and D is the damping constant.

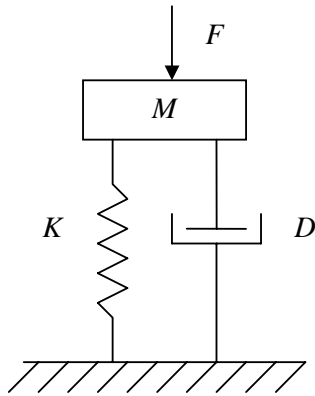


Fig. 1 The classical spring-mass-damper system

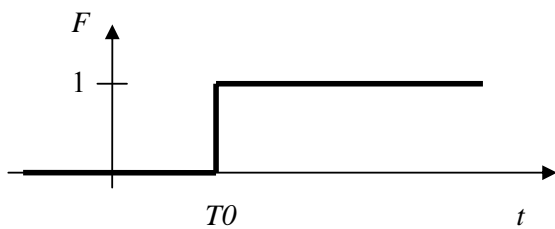
The mathematical model of the classical spring-mass-damper system, shown in Fig. 1, may be written by the following state-space differential equations:

$$\begin{aligned} \frac{dx}{dt} &= v \\ \frac{dv}{dt} &= -\frac{K}{M} \cdot x - \frac{D}{M} \cdot v + \frac{F}{M} \end{aligned} \quad (1)$$

where x is the position of the mass M and v is the velocity of the mass. Further, let us assume that the initial conditions are the following:

$$x(0) = 0, \quad v(0) = 0$$

Further, let us assume that force F is the step input shown in Fig. 2 (step time = 10, initial value = 0, final value = 1).

Fig. 2 The step input F

The program for the classical spring-mass-damper system (Fig. 1) written in GODYS-PC based on the state-space differential equations (1) is shown in Fig. 3.

```

MODEL SPRING
PREPARE F, x
PARAMT K, D, M, t0, A
DYNAMIC
x = INTEG(v; 0)
v = INTEG(-(K/M) * x - (D/M) * v + (F/M); 0)
F = A * STEP(t - t0)
END

LOAD SPRING
DATA K = 1, D = 0.3, M = 1, A = -1, t0 = 10
EXECUTE(DT = 0.1, METHOD = TRAPEZ, @
        TMAX = 50, COMDEL = 0.2)
PLOTXY(t, F)
PLOTXY(t, x)
FINISH

```

Fig. 3 The program for the classical spring-mass-damper system (Fig. 1) in GODYS-PC

Now for some explanation about program itself. Elements shown in upper case can be written in lower case and vice versa. The statement **MODEL** identifies the model. The statement **PREPARE** specifies which variables are to be collected for latter printing or plotting. The statement **PARAMT** declares identifiers parameters of the model. The statement **DYNAMIC** identifies the beginning of the dynamic section. The dynamic section comprises a set of equations defining the model. The statement **DYNAMIC** must be accompanied the matching statement **END**. In the example used here the dynamic section contains standard functions **INTEG** and **STEP**.

The statement **LOAD** identifies the beginning of runtime commands. The statement **LOAD** must be accompanied the matching statement **FINISH**. The statement **DATA** is used to assign values to parameters of the model. The statement **EXECUTE** initiates the run. The parameter **DT** is the integration step size. The parameter **METHOD** specifies the name for the integration algorithm. The parameter **TMAX** specifies the end of the simulation. The parameter **COMDEL** is the interval size for printing and plotting simulation results. The statement **PLOTXY(t, F)** creates a plot of the force F versus time t . Similarly, the statement **PLOTXY(t, x)** creates a plot of the position x of the mass M , versus time t . The outputs of the **PLOTXY(t, F)** and **PLOTXY(t, x)** statements are shown in Fig. 4 and in Fig. 5 respectively.

For comparison the use of GODYS-PC with the use of Simulink®, a model for the same classical spring-mass-damper system (Fig. 1) described in Simulink® is shown in Fig. 6. Fig. 7 shows a plot of the force F versus time t generated by Simulink® for the model shown in Fig. 6. Similarly, Fig. 8 shows a plot of the position x of the mass M , versus time t generated by Simulink® for the model shown in Fig. 6.

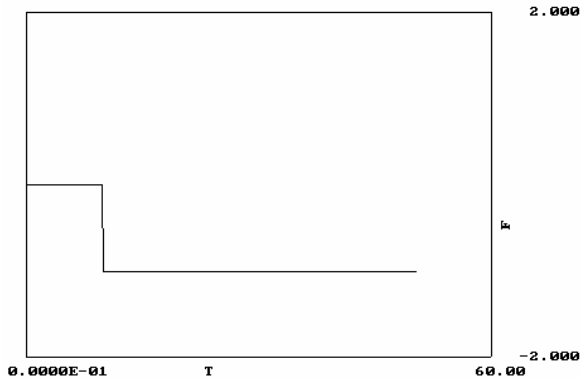


Fig. 4 The output of the PLOTXY(t, F) statement

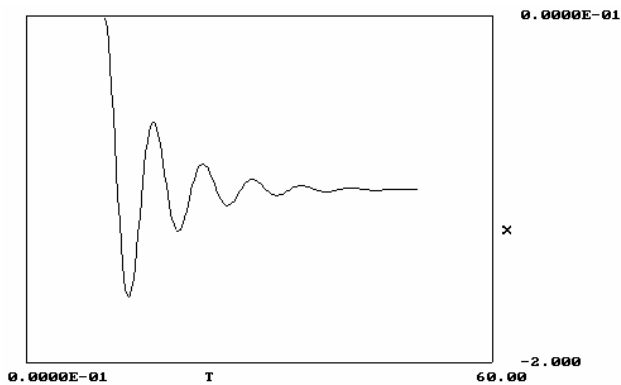


Fig. 5 The output of the PLOTXY(t, x) statement

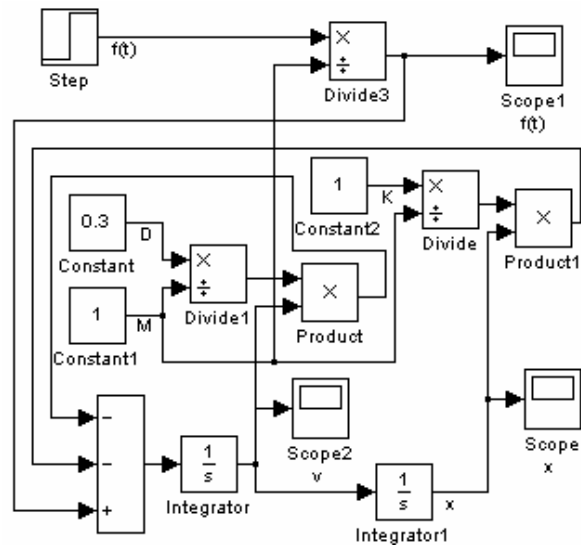
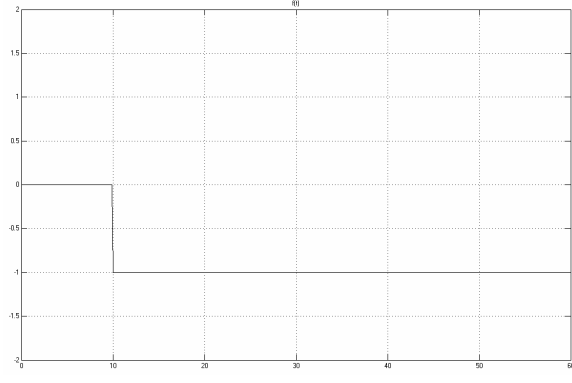
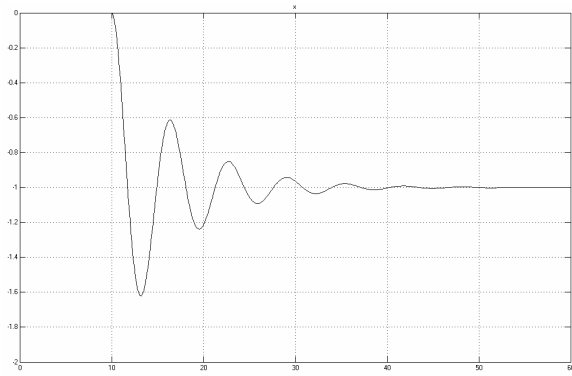
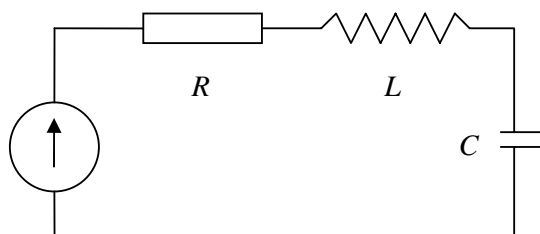


Fig. 6 A model for the classical spring-mass-damper system (Fig. 1) described in Simulink®

Now, let us consider the following classical electrical circuit RLC shown in Fig. 9, where R is the resistance, L is the inductance, C is the capacitance and E is the voltage. Further, let us assume that the voltage E is the step input.


Fig. 7 The plot of F versus time t generated by Simulink®

Fig. 8 The plot of x versus time t generated by Simulink®

Fig. 9 The classical electrical circuit RLC

The mathematical model of the classical electrical RLC circuit shown in Fig. 9 may be written by following state-space differential equations :

$$\begin{aligned} \frac{dq}{dt} &= i \\ \frac{di}{dt} &= -\frac{R}{L} \cdot i - \frac{1}{C} \cdot q + \frac{E}{L} \end{aligned} \quad (2)$$

where i is the current. Further, let us assume that the initial conditions are the following:

$$q(0) = 0, \quad i(0) = 0$$

The program for the classical electrical circuit *RLC* system (Fig. 7) written in GODYS-PC based on the state-space differential equations (2) is shown in Fig. 10.

```

MODEL RLC
PREPARE E, i
PARAMT t0, R, i, C
DYNAMIC
E = STEP(t - t0)
q = INTEG(i; 0)
i = INTEG((E/L) - (R/L)*i - (1/(L*C))*q); 0)
END

LOAD RLC
DATA t0 = 20, R = 1, L = 1, C = 1
EXECUTE(DT = 0.1, TMAX = 50, COMDEL = 0.1)
PLOTXY(t = (0, 50), E = (0, 2))
PLOTXY(t, i)
FINISH

```

Fig. 10 The program for the classical electrical circuit *RLC* (Fig. 7) in GODYS-PC

The output of the PLOTXY($t = (0, 50)$, $E = (0, 2)$) shown in Fig. 11 creates a plot of the voltage E versus time t . Similarly, the output of the PLOTXY(t, i) shown in Fig. 12 creates a plot of the current i versus time t .

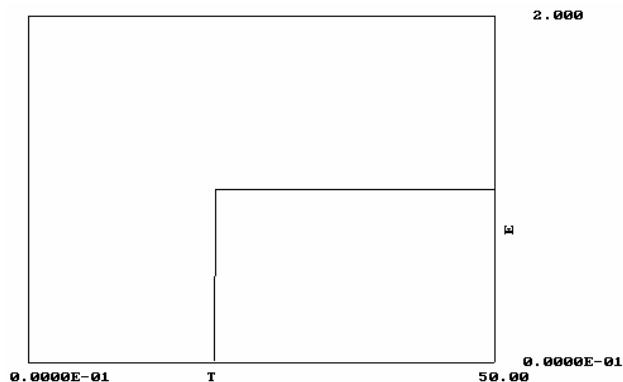


Fig. 11 The output of the PLOTXY($t = (0, 50)$, $E = (0, 2)$) statement

For comparison the use of GODYS-PC with the use of Simulink®, a model for the same classical electrical circuit *RLC* (Fig. 9) described in Simulink® is shown in Fig. 13. Fig. 14 shows a plot of the current i versus time t generated by Simulink® for the model shown in Fig. 13.

Now, let us consider a control loop block diagram shown in Fig. 15 ([11]).

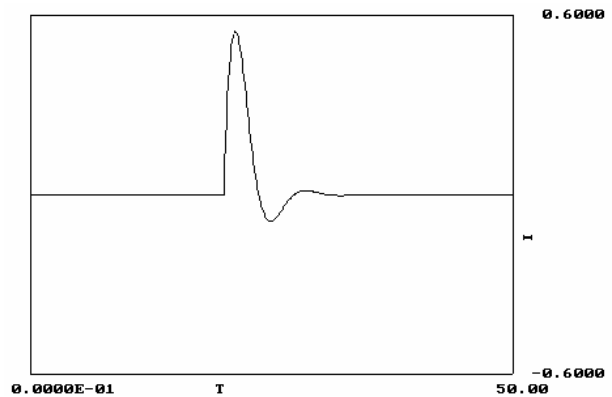


Fig. 12 The output of the PLOTXY(t, i) statement

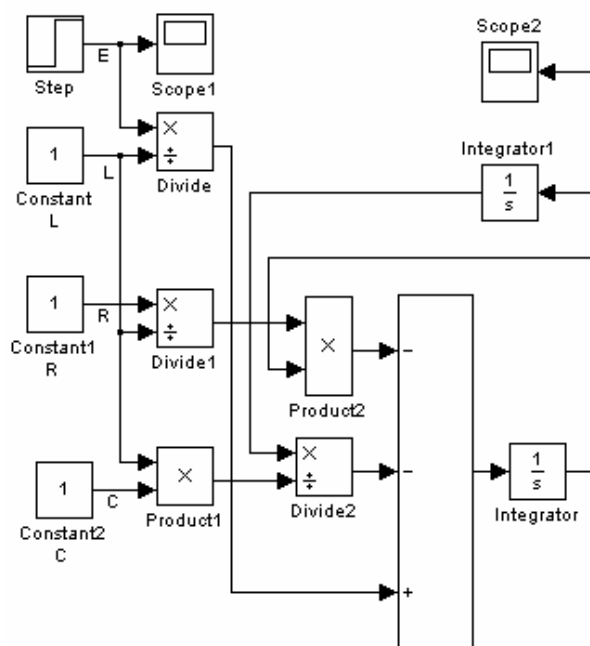


Fig. 13 A model for the classic electrical circuit *RLC* (Fig. 9) described in Simulink®

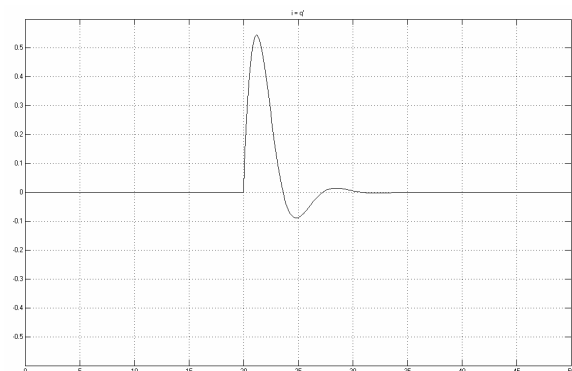


Fig. 14 The plot of i versus time t generated by Simulink®



Fig. 15 A control loop block diagram

Further let us assume that the parameter $k \in (5, 25)$ has to be determined such that the following cost function:

$$F = \int_0^{\infty} e^2 dt$$

is minimal.

The description of a model of the control loop block diagram (Fig. 15) in GODYS-PC is shown in Fig. 16.

```

MODEL CONTROL
PREPARE x, y, e, F
PARAMT k, t0
DYNAMIC
x = STEP(t - t0)
e = x - y
u = k*REALPL(e; 8, 0)
y = REALPL(0.01*INTEG(u; 0); 2, 0)
f = INTEG(e*e; 0)
END

LOAD CONTROL
DATA t0 = 20
EXECUTE(tmax = 175, dt = 0.1, comdel = 0.1, @
      opt = (F(k = (5, 25)), alg = mgs, lim = 10))
PLOTXY(t, x)
PLOTXY(t, y)
PLOTXY(t, e)
PLOTXY(t, F)
FINISH

```

Fig. 16 The program for the control loop block diagram (Fig. 15) in GODYS-PC

In the example used here the dynamic section contains the following standard function:

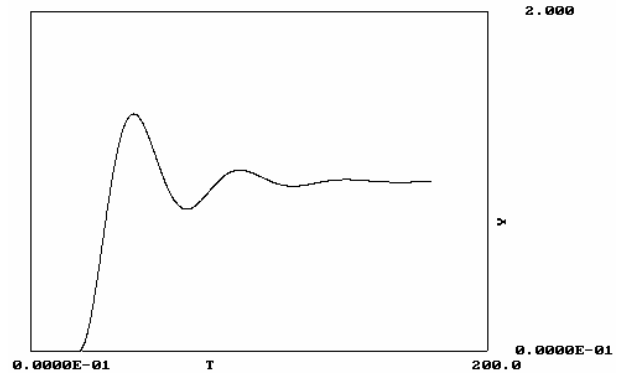
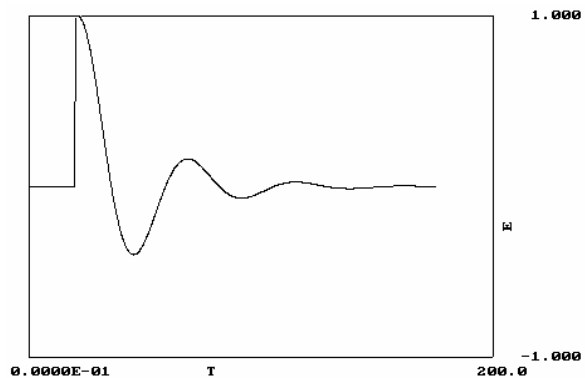
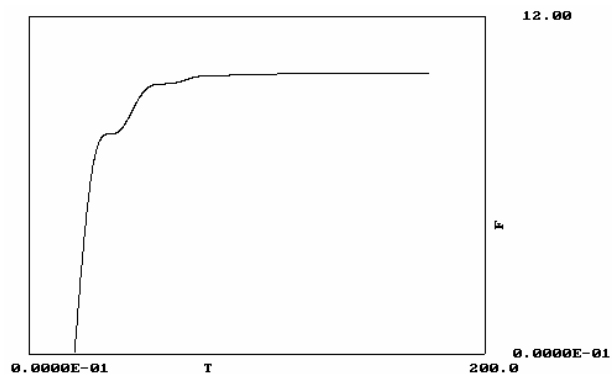
$$y = \text{REALPL}(x; a, y_0)$$

which produces the first order lag, where output y is related to input x through the following transfer function:

$$\frac{x}{y} = \frac{1}{a \cdot s + 1}$$

where $y_0 = y(0)$. The parameter **opt** in the statement **EXECUTE** initiates parameter optimization. The parameter **alg** specifies a method for a cost function minimization algorithm. Each a cost function evaluation involves a simulation run. The parameter **lim** specifies a number of

runs during parameter optimization. The minimal value 9.958 of the cost function F has been found for $k = 17.36$. The outputs of the **PLOTXY(t, y)**, **PLOTXY(t, e)** and **PLOTXY(t, F)** statements are shown in Fig. 17, Fig. 18 and Fig. 21 respectively.

Fig. 17 The output of the **PLOTXY(t, y)** statementFig. 18 The output of the **PLOTXY(t, e)** statementFig. 19 The output of the **PLOTXY(t, F)** statement

For comparison the use of GODYS-PC with the use of Simulink®, a model for the same control loop block diagram (Fig. 15) described in Simulink® is shown in Fig. 20.

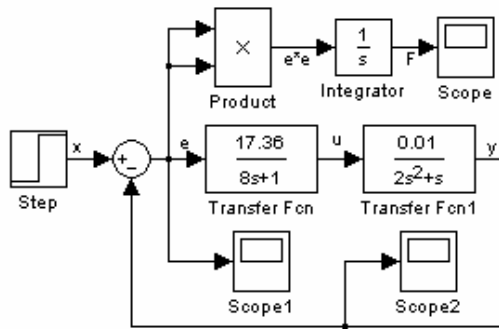


Fig. 20 A model for the control loop block diagram (Fig. 15) described in Simulink®

The plots of y , e and F versus time t generated by Simulink® for the model of the control loop block diagram (Fig. 20) are shown in Fig. 21, Fig. 22 and Fig. 23 respectively.

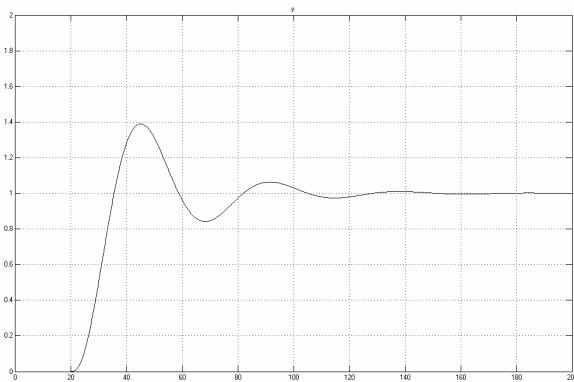


Fig. 21 The plot of y versus time t generated by Simulink®

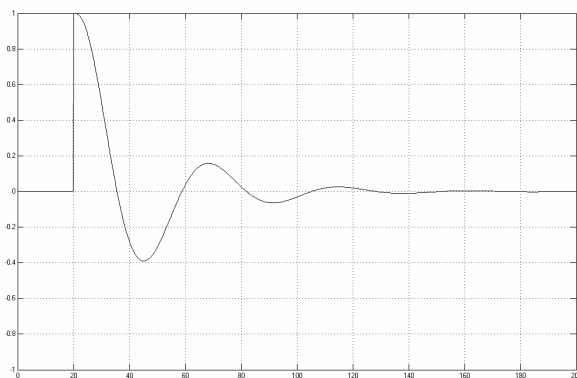


Fig. 22 The plot of e versus time t generated by Simulink®

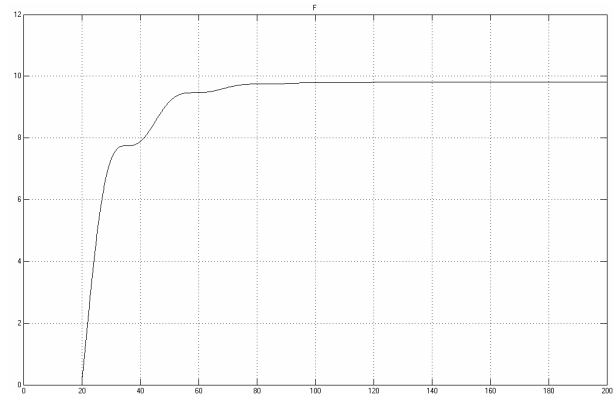


Fig. 23 The plot of F versus time t generated by Simulink®

III. CONCLUSION

In this paper we have presented GODYS-PC software package for modeling, simulating and analyzing dynamic systems. The basic structure of GODYS-PC follows the CSSL standard. GODYS-PC meets requirements needed for a good continuous simulation language. Typical areas in which GODYS-PC may be applied come from a wide diversity of realistic situations in engineering, control system design, economics, biology and so on. GODYS-PC is easy to learn even for somebody who is not an experienced programmer. In order to compare GODYS-PC with widely used in academia and industry Simulink®, the same examples has been provided both in GODYS-PC and Simulink®.

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