Control Volume 1 HRPC

## Governing Equations

$$\dot{n}_{ox,v} + \dot{n}_{ox,l} = -C_d N_{inj} A_{inj} \sqrt{\frac{2(P_T - P_{losses} - P_C)}{(MW)_{ox} \overline{V}_{ox,l}}}$$

$$-\overline{V}_{ox,l}P_{cr,ox}\dot{n}_{ox,l} + \left(\left(V_T - n_{ox,l}\overline{V}_{ox,l}\right)\left(\frac{P_{cr,ox}}{dT}\right) - n_{ox,l}P_{cr,ox}\left(\frac{\overline{V}_{ox,l}}{dT}\right)\right)\dot{T}_T = R_u\left(n_{ox,v}\dot{T}_T + T_T\dot{n}_{ox,v}\right)$$

$$(m_T c_{P_T} + n_{ox,l} \overline{C}_{P_{ox,l}} + n_{ox,v} \overline{C}_{V_{ox,v}} + n_{sp,v} \overline{C}_{V_{sp,v}}) \dot{T}_T = \dot{n}_{ox,v} (R_u T_T - \Delta \overline{H}_{ox,v}) + \dot{n}_{ox,l} (P_T \overline{V}_{ox,l})$$

The unknowns are  $\dot{n}_{ox,l},\,\dot{n}_{ox,v}$  and  $\dot{T}_T$ 

And so we proceed to solve the equations to isolate each of the unknowns:

$$\dot{n}_{ox,v} = \frac{\sqrt{2}A_{\rm inj}C_dN_{\rm inj}\sqrt{-\frac{P_C+P_{\rm losses}-P_T}{\rm MW_{ox}\bar{V}_{ox,l}}}\left(\bar{V}_{\rm ox,l}\left(P_{\rm cr,ox}\left(n_{\rm ox,l}\bar{C}_{P_{\rm ox,l}}+n_{\rm ox,v}\bar{C}_{V_{\rm ox,v}}+n_{\rm sp,v}\bar{C}_{V_{\rm ox,v}}\right)\right)}{m_Tc_{P_T}\left(T_TR_u-P_{\rm cr,ox}\bar{V}_{\rm ox,l}\right)+R_u\left(T_T\left(n_{\rm ox,l}\left(\bar{C}_{P_{\rm ox,l}}-\bar{V}_{\rm ox,l}P_{\rm cr,ox,dT}-P_{\rm cr,ox}\bar{V}_{\rm ox,l,dT}\right)+n_{\rm ox,v}\bar{C}_{V_{\rm ox,v}}+n_{\rm sp,v}\bar{C}_{V_{\rm sp,v}}+V_{T_{\rm ox,v}\bar{C}_{V_{\rm ox,v}}}\right)\right)}$$