

Release Notes for SimMechanics™

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Release Notes for SimMechanics™

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No New Features or Changes

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No New Features or Changes

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R2012b

Version: 4.1
New Features: Yes
Bug Fixes: No

Second Generation technology now supporting CAD import from SolidWorks, Inventor, and Pro/ENGINEER

SimMechanics™ introduces CAD import in SimMechanics second-generation format. Import the SimMechanics Import XML file that represents a CAD assembly, and automatically generate the corresponding SimMechanics second-generation model.

Second Generation technology now supporting C-code generation with Simulink Coder

SimMechanics Second Generation now supports code generation with Simulink® Coder. Generate C code from a SimMechanics model, and use the code for applications like hardware-in-the-loop (HIL) testing and rapid prototyping.

SimMechanics Second Generation does not support run-time parameters. Model parameters are fixed during code generation, and are not available for edit outside SimMechanics. To update model parameters, you must edit them in SimMechanics and then regenerate the C code for your model.

Solid of revolution geometry in Solid block

The Solid block adds a Revolution geometry. The geometry represents solids that have a constant cross-section about an axis of revolution. Examples include cones, domes, and toroids. Revolutions can be full or partial.

Changes to inertia specification

Compatibility Considerations: Yes

The form of the **Products of Inertia** input vector has changed in Solid and Inertia blocks. The new input vector now has the form $[I_{yz}, I_{zx}, I_{xy}]$. You can extract the products of inertia directly from the off-diagonal elements of the inertia tensor.

$$\begin{bmatrix} I_{xx} & I_{xy} & I_{xz} \\ I_{xy} & I_{yy} & I_{yz} \\ I_{xz} & I_{yz} & I_{zz} \end{bmatrix}$$

Previously, the **Products of Inertia** parameter required the negative values of I_{yz} , I_{zx} , and I_{xy} .

Four new examples

SimMechanics introduces four new examples:

- Radial Piston Engine
- Electrically Operated Bread Slicer
- CAD Import of Stewart Platform
- CAD Import of Four-Bar Mechanism

R2012a

Version: 4.0
New Features: Yes
Bug Fixes: No

SimMechanics Version 4.0 Software and Second Generation Technology

SimMechanics Version 4.0 introduces Second Generation technology to model, simulate, and analyze two- and three-dimensional multi-body mechanical systems. Second Generation technology provides a more intuitive and powerful block diagram language that lets you easily create reusable parts and libraries. It also adds advanced three-dimensional visualization and animation support.

Version 4.0 provides full support for both First Generation and Second Generation functionality, including block sets and tools. With Version 4.0, you have the option to create and simulate a mechanical model using First or Second Generation technology. Version 4.0 software gives you the two full block libraries, labeled First Generation and Second Generation.

Note The term *generation* — e.g. “Second *Generation*” — refers to the SimMechanics technology used. A SimMechanics *version* may contain one or both *generations*.

SimMechanics First and Second Generation Technologies

Compatibility Considerations: Yes

SimMechanics Second Generation technology is a comprehensive advancement of SimMechanics First Generation technology. To ease the transition from First Generation to Second Generation technology, and to support existing First Generation users, SimMechanics Version 4.0 fully supports *both* First Generation and Second Generation features.

This table summarizes First Generation and Second Generation technologies in their native SimMechanics versions.

Technology	Description	Block Library
SimMechanics First Generation	Encompasses the complete SimMechanics behavior through Version 3.2.3 (R2011b). First Generation features are designated by the First Generation library in both the Simulink Library Browser and the Help Browser windows.	To access the block library, at the command line, type <code>mechlib</code> .
SimMechanics Second Generation	Encompasses the new SimMechanics behavior in Version 4.0 (R2012a). Second Generation features are designated by the Second Generation library in both the Simulink Library Browser and the Help Browser windows.	To access the block library, at the command line, type <code>sm_lib</code> .

Compatibility Considerations

First and Second Generation blocks are based on different block diagram languages. To connect a First Generation block to a Second Generation block, you must use a Simulink signal.

Improvements in SimMechanics Second Generation Technology

The following functionality has been added or improved for SimMechanics Second Generation:

- A block diagram language based on coordinate frames
 - Ports and nodes map directly to frames.
- A new mechanical modeling paradigm centered on coordinate frames
 - Frames are locally defined.
- Advanced visualization support using the Mechanics Explorer utility
 - Visualize a three-dimensional mechanical model.
 - Explore your model using multiple simultaneous views.
 - Easily navigate your model using an hierarchical tree browser.
- Enhanced animation support
 - Control the speed of your animation.
 - Replay your animation without rerunning the simulation.
- Advanced parameter specification options
 - Automatically calculate mass and inertia for simple and compound geometries.
 - Specify priority settings for the model initial conditions.
- Improved integration with Simscape™.
 - Includes support for physical signals and units.

Common Functionality in SimMechanics First and Second Generation Technologies

The following functionality is present in both SimMechanics First and Second Generations:

- Rigid body specification
- Joint specification
- Constraint specification
- Force and torque inputs
- Linearization of mechanical models
- Trimming mode of analysis
- Motion outputs

Functionality Found Only in SimMechanics First Generation Technology

The following functionality is present only in SimMechanics First Generation:

- Code generation support
 - Model reference accelerator mode is absent in the SimMechanics Second Generation sub-library.
- CAD import support
- Motion input in Joint Blocks
- Force outputs in **Joints** and **Constraints** blocks
- Missing **Constraints** blocks:
 - *point-curve*, *gear*, *velocity*, and *projection* constraints are not included in the SimMechanics Second Generation sub-library.
- Missing Force Outputs
 - Applied and reaction force outputs for joints are not available.
- Missing Joints
 - *Screw* and *massless connector* joint blocks are not included in the SimMechanics Second Generation sub-library.
- Variable gravity and mass distribution
- Visualization features
 - Model reference normal mode is not included in SimMechanics Second Generation technology.

R2011b

Version: 3.2.3
New Features: No
Bug Fixes: Yes

R2011a

Version: 3.2.2
New Features: No
Bug Fixes: No

No New Features or Changes

R2010b

Version: 3.2.1
New Features: No
Bug Fixes: No

No New Features or Changes

R2010a

Version: 3.2
New Features: Yes
Bug Fixes: No

Optional Simplification of Subsystem Hierarchy During Model Import

When you generate SimMechanics models with the `mech_import` command, you can now choose certain automatic simplifications of the imported model's hierarchy:

- Bringing all joints in the generated model to the highest level being imported, either the whole model or a subsystem.
- Grouping all welded bodies at each level of the model hierarchy into new rigid subsystems at the same level.

Without these options, the generated model's hierarchy follows the hierarchy specified in the imported XML file, derived from its original CAD assembly.

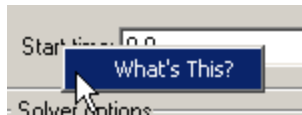
"What's This?" Context-Sensitive Help Available for Import Physical Modeling XML Dialog Box

This release introduces "What's This?" context-sensitive help for parameters that appear in the Import Physical Modeling XML dialog opened by entering `mech_import` with no arguments at the command line. This feature provides quick access to a detailed description of the parameters, saving you the time it would take to find the information in the Help browser.

To use the "What's This?" help, do the following:

- 1 Place your cursor over the label of a parameter.
- 2 Right-click. A **What's This?** context menu appears.

For example, the following figure shows the **What's This?** context menu appearing after a right-click on the **Start time** parameter in the **Solver** pane.



- 3 Click **What's This?** A context-sensitive help window appears showing a description of the parameter.

Connection Port Block Consolidated to Simscape Library and Documentation

The Connection Port block has been removed from the block libraries of all add-on products dependent on Simscape software. When using these dependent add-on products, look for the Connection Port block in the Simscape Utilities library.

The Connection Port block help for these add-on products now directs you to the Simscape block reference.

New Demos

Two new demos have been added.

Model Hierarchy Simplification During Import

You can learn more about how to simplify imported model hierarchy by reviewing the new demo page.

This demo uses two new Physical Modeling XML files, `SimplificationExample1.xml` and `SimplificationExample2.xml`. Models generated from these XML files also appear as large graphics examples in Nondefault Hierarchy and Organization of Generated Models.

Reference Coordinate Systems in Imported Physical Modeling XML

With the SimMechanics Link utility, you can export reference coordinate systems that you insert into CAD assemblies. (This feature is not supported on all CAD platforms.) From the exported Physical Modeling XML, you can generate a SimMechanics model with extra Body coordinate systems corresponding to the assembly reference coordinate systems and not associated with CAD constraints and automatically generated Joints.

Using the new `GearAssembly.xml` file, the new demo page explains how you can use reference coordinate systems to help you manually add a Constraint block to a model after import.

R2009b

Version: 3.1.1
New Features: No
Bug Fixes: No

No New Features or Changes

R2009a

Version: 3.1
New Features: Yes
Bug Fixes: No

Changes to External Virtual Reality Visualization

The new Simulink 3D Animation™ software replaces the Virtual Reality Toolbox™ product for visualizing virtual scenes. The documentation section on building and using a virtual reality client to visualize SimMechanics models has been updated to reflect this change.

Pro/ENGINEER CAD Translation Case Study

The CAD translation chapter now contains a case study demonstrating assembly export and re-export, along with model import and update. The study uses SimMechanics and SimMechanics Link software, together with Pro/ENGINEER®, and models a double pendulum, subsequently modified to a triple pendulum. The study illustrates how you can update an existing generated CAD-based model with successive changes to the original CAD assembly.

R2008b

Version: 3.0
New Features: Yes
Bug Fixes: No

New SimMechanics Visualization and Animation

Compatibility Considerations: Yes

The visualization has been upgraded with new features and a new interface. It now supports

- Customizable body geometries with STL (stereolithographic) files
- Customizable body colors
- Better dynamic view control
- Better animation speed control

Consult the new *SimMechanics Visualization and Import Guide* for complete information.

For more about creating STL files, see “BodyBuilder for Creating STL Body Geometry Files” on page 38.

Compatibility Considerations

The old SimMechanics visualization allowed you to save visualization settings to a MAT-file associated with a SimMechanics model.

When you open such a model in the new version, the model will attempt to load the MAT-file, as before, and map the old visualization options to the new options as closely as possible. This is a one-time conversion. The MAT-file has to be on the MATLAB® path so it can be found when you open the model.

To save these converted visualization settings:

- 1 You must open the visualization window and save these settings to the model.
- 2 Then you must save the model itself.

Use the visualization controls to save the settings to the model. See the *SimMechanics Visualization and Import Guide*.

Caution To save visualization settings from an old model in the new visualization, you must follow these steps, in this order. Otherwise, you might lose the old settings permanently.

Compressed Animation Recording from New Visualization on Windows Vista and 64-Bit Windows Operating Systems

To compress a recorded animation of a simulation, you need the Indeo 5 codec. This codec might not be available on the 32-bit Windows Vista™ operating system and the 64-bit Windows® XP and Windows Vista operating systems. If you require compression and the codec is not found, the animation AVI file is still saved, but without compression. A warning appears.

For further details, consult Technical Solution 1-1HTNHW at the MathWorks® web site.

New Visualization Window Status Bar Not Available on Intel Mac Operating System

The status bar of the new visualization window, below the machine display, does not appear at all on the Intel® Mac operating system. On other operating systems, the status bar shows simulation time, as well as Body block and coordinate system names.

New Visualization Not Supported on Solaris 64 UNIX Operating System

The new visualization and animation interface is not available on the Solaris 64 UNIX operating system. SimMechanics software automatically reverts to the old visualization interface.

New SimMechanics Link Utility

The new SimMechanics Link utility provides a bridge from third-party mechanical design and modeling applications to the system and control design features of MATLAB and Simulink. It connects computer-aided design (CAD) platforms to mechanical modeling with SimMechanics software by enabling export of CAD assemblies into the Physical Modeling XML format that allows for automatic generation of SimMechanics models.

Refer to the SimMechanics Link documentation for more information. The SimMechanics Link utility requires MATLAB, but not Simulink, Simscape, or SimMechanics.

Upgraded Mechanical Import and Automatic Model Generation

Compatibility Considerations: Yes

The new `mech_import` command works with externally defined Physical Modeling XML files to automatically generate SimMechanics models. It supports a new SimMechanics feature, updating models generated previously.

Compatibility Considerations

Physical Modeling XML files generated by the old CAD-to-SimMechanics translators remain compatible with `mech_import`. Using this command, you can still import old XML files to generate SimMechanics models. Because these models have no associated exported STL body geometry files, they will visualize using the standard (noncustom) body shapes.

The updating feature of `mech_import` works only with Physical Modeling XML files generated by exporting from the SimMechanics Link utility. This feature does not work with Physical Modeling XML files generated from the old CAD-to-SimMechanics translators.

You should replace all existing instances of the `import_physmod` command with the new `mech_import` command. See “Command Being Removed” on page 39.

Caution Do not attempt to use the `import_physmod` command in older SimMechanics versions with Physical Modeling XML files generated by the new SimMechanics Link exporter.

BodyBuilder for Creating STL Body Geometry Files

In addition to generating STL body geometry files automatically from a CAD assembly, you can also create STL files by hand or by using a body geometry editor. BodyBuilder is an application based on MATLAB that provides a graphical means to create STL files for use in SimMechanics body visualization. You can obtain BodyBuilder from MATLAB Central.

Command Being Removed

Compatibility Considerations: Yes

Command Name	What Happens When You Use Command?	Use This Instead	Compatibility Considerations
import_physmod	Still runs	mech_import	Replace all existing instances of import_physmod with mech_import.

SimMechanics Documentation Reorganized

The SimMechanics documentation is now organized into four books.

Book	Includes Material from Old Chapters
SimMechanics Getting Started Guide	1, 2, and 3
SimMechanics User’s Guide	4, 5, 8, and 9
SimMechanics Visualization and Import Guide	6 and 7
SimMechanics Reference	10, 11, 12, and 13

Physical Modeling of Mechanical Friction

A recent MATLAB Digest article explains how to simulate mechanical friction with Simulink, SimDriveline™, and SimMechanics models. A set of models accompanies the article in a compressed zip archive available from MATLAB Central.

R2008a

Version: 2.7.1
New Features: Yes
Bug Fixes: No

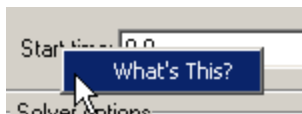
“What’s This?” Context-Sensitive Help Available for Simulink Configuration Parameters Dialog

R2008a introduces “What’s This?” context-sensitive help for parameters that appear in the Simulink Configuration Parameters dialog. This feature provides quick access to a detailed description of the parameters, saving you the time it would take to find the information in the Help browser.

To use the “What’s This?” help, do the following:

- 1 Place your cursor over the label of a parameter.
- 2 Right-click. A **What’s This?** context menu appears.

For example, the following figure shows the **What’s This?** context menu appearing after a right-click on the **Start time** parameter in the **Solver** pane.



- 3 Click **What’s This?** A context-sensitive help window appears showing a description of the parameter.

R2007b

Version: 2.7
New Features: Yes
Bug Fixes: No

Interfacing with One-Dimensional Simscape Domains

The Prismatic-Translational Interface and Revolute-Rotational Interface blocks of the new Interface Elements library allow you to connect a SimMechanics Prismatic or Revolute joint primitive to a Physical Networks line connected to Simscape blocks. The Prismatic-Translational Interface and Revolute-Rotational Interface blocks transfer mechanical velocities and forces/torques as Physical Networks cross- and through-variables, respectively, without energy loss, along or around axes that you can define.

Several new demos illustrate the use of the Interface Elements blocks. See [New Demos](#).

SimMechanics State Names Now Available to Simulink and Real-Time Workshop

You can access the names of the mechanical states of your SimMechanics models through the `mech_stateVectorMgr` command. The names of these states and the SimMechanics blocks that define them are now available to Simulink and appear in the outputs of model simulations. They also appear in simulations based on code generated with Real-Time Workshop.

See the Simulink and Real-Time Workshop documentation for further details about states.

Controlling Redundant Constraint Analysis with New Tolerance Setting

You can now adjust the sensitivity of the SimMechanics redundant constraint analysis in the **Constraints** tab of the Machine Environment block, which allows you to choose between automatic constraint redundancy analysis or specifying a constraint redundancy tolerance explicitly.

Certain mechanical configurations are sensitive to the constraint redundancy tolerance and can spuriously lose or gain degrees of freedom if this tolerance is adjusted incorrectly.

New Demos

Nine new demos have been added.

Interface Blocks

These demos illustrate how to use the new Interface Elements blocks. See [Interfacing with One-Dimensional Simscape Domains](#).

- `mech_interface_crate_transfer`
- `mech_interface_dspring_damper`
- `mech_interface_hyd_cylinder`
- `mech_interface_hyd_slidercrank`
- `mech_interface_rot_spr_damper`
- `mech_interface_trans_spr_damper`

Car Modeling

These new demos provide examples of sophisticated automotive modeling.

- `mech_car_handling`
- `mech_car_kinematics`

These demos shipped in the Version 2.6 (R2007a) SimMechanics product.

Code Generation Documentation Consolidated to Simscape User's Guide

Documentation of code generation features common to all Physical Modeling add-on products based on Simscape software has been consolidated to the *Simscape User's Guide*. The *SimMechanics User's Guide* continues to document uniquely SimMechanics features related to code generation.

R2007a

Version: 2.6
New Features: Yes
Bug Fixes: No

SimMechanics Software Now Requires Simscape Product

SimMechanics software now depends on and requires Simscape software, the foundation for Physical Modeling products. Simscape software includes common Physical Modeling utilities and block libraries.

Sharing Models Using Simscape Editing Modes

SimMechanics software now features a selection of two Simscape editing modes that allow full or restricted editing of models.

- The Restricted mode requires SimMechanics product to be installed, but does not require a license. It allows you to change a limited set of model parameters, but not the blocks or connections, in a SimMechanics model.
- The Full mode requires both Simscape and SimMechanics products to be installed. It allows you to change anything in a SimMechanics model.

Block Library Links Must Be Resolved

Compatibility Considerations: Yes

All SimMechanics blocks in your models must now have resolved block library links. You can neither disable nor break these library links. This is a global Simscape requirement. Consult the Simscape documentation for further details.

Compatibility Considerations

If you have an existing SimMechanics model with disabled or broken links from SimMechanics blocks to the SimMechanics block library, you must restore all the broken block library links for your model to be valid.

If you have disabled or broken the SimMechanics library link for blocks that you have customized and want to keep these modified blocks in your model, you must move these modified blocks to your own custom library or libraries, then copy the block instances that you need to your model.

You must still restore the block link to its parent library, whether that parent is the SimMechanics block library or your own.

Two Blocks Now with Tunable Parameters

These SimMechanics parameters are now tunable from their respective block dialogs:

- The **Gravity vector** field of the Machine Environment block.
- All three parameter fields of the Body Spring & Damper block.

Demos Expanded

Five new demos have been added.

Angular Motion Equivalence

The `mech_gimbal_transform` demo shows the equivalence of a body's angular motion as measured by Joint Sensors and as measured by Body Sensors.

Joint Limits

Two demos illustrate how to model limits or clearance on joint motion:

- `mech_jointlimit_prismatic`
- `mech_jointlimit_revolute`

The first illustrates limits on translational motion; the second, limits on rotational motion.

Stochastic Oscillator and Controller

Two demos simulate a mixture of deterministic and random forces with a model of a micromechanical damped linear oscillator:

- `mech_brownian_osc`
- `mech_brownian_osc_control`

The first model has no controller; the second, a control force in addition to the damped spring and white noise forces.

Modeling Constraints with SimMechanics Software

A new MATLAB Digest article explains how to model mechanical constraints with SimMechanics blocks. The article uses a set of four existing SimMechanics demos as illustrations.

R2006b

Version: 2.5
New Features: Yes
Bug Fixes: No

Computer-Aided Design Translator for Pro/ENGINEER Available via the Web

Compatibility Considerations: Yes

A new computer-aided design (CAD) Pro/ENGINEER-to-SimMechanics translator is available. You install and use this translator with Pro/ENGINEER. It is independent of MATLAB.

The translator converts a Pro/ENGINEER CAD machine assembly into an XML file in the Physical Modeling format. The XML file represents the assembly in a form that you can use to generate a SimMechanics block diagram model dynamically equivalent to the original CAD assembly. To generate models, use the `import_physmod` command.

Installing the Pro/ENGINEER-to-SimMechanicsTranslator

Obtain and use the installer executable by locating and downloading its archive at www.mathworks.com/products/simmechanics/. A README page is provided that describes installation and configuration details.

Translator Documentation

Help files accompany the Pro/ENGINEER-to-SimMechanics translator. They include two HTML pages and a PDF book. These files are independent of the MATLAB help system.

Translator Examples

Some examples of Pro/ENGINEER CAD assemblies are included with the Pro/ENGINEER-to-SimMechanics translator.

One of the examples is a robot arm assembly. The corresponding XML file in Physical Modeling format, `robot.xml`, is located in the `toolbox/physmod/mech/mechdemos/` folder, relative to your MATLAB root.

Compatibility Considerations

Versions of Pro/ENGINEER compatible with the Pro/ENGINEER-to-SimMechanics translator are listed at the MathWorks

Web site. The translator is available only for the Microsoft Windows (32-bit) operating system.

SolidWorks-to-SimMechanics Translator Now Available Only via the Web

Compatibility Considerations: Yes

The existing SolidWorks®-to-SimMechanics translator for the SolidWorks CAD platform continues to be available via the Web, at www.mathworks.com/products/simmechanics/. However, it no longer ships with the SimMechanics product.

Compatibility Considerations

Versions of SolidWorks compatible with the SolidWorks-to-SimMechanics translator are listed at the MathWorks Web site.

The SolidWorks CAD platform and the SolidWorks-to-SimMechanics translator are available only for the Microsoft Windows (32-bit) operating system.

New Demo

This version of SimMechanics software includes one new demo model, `mech_brownian_osc`, a stochastic linear harmonic oscillator based on micro- and biomechanics.

Modeling Flexible Bodies with SimMechanics Software

A new MATLAB Digest article and related technical paper explain how to simulate flexible bodies with SimMechanics models and third-party finite element analysis applications. A set of models accompanies the technical paper in a compressed zip archive available from MATLAB Central.

R2006a

Version: 2.4
New Features: Yes
Bug Fixes: No

New Block Dialogs and the Simulink Model Explorer

Most of the SimMechanics block dialogs have been upgraded and are now compatible with the Simulink Model Explorer. See the Simulink documentation for more about Model Explorer.

Block Dialogs Not Rendered in Model Explorer

Model Explorer cannot render the dialogs of these blocks:

- Shared Environment
- Point-Curve Constraint

Joint Spring & Damper Adds Extra Simulink State When Connected to a Revolute

Each Joint Spring & Damper block connected to a revolute primitive now adds a Simulink state to your model. These states are in addition to other normal Simulink states, such as those associated with Integrator and Transfer Fcn blocks. See the Simulink documentation for more about Simulink model states.

This new feature does not change the mechanical states of your model, those associated with SimMechanics joint blocks. See the `mech_stateVectorMgr` command reference for more about mechanical states.

Improved SolidWorks CAD Translation

The SolidWorks-to-SimMechanics translator and Physical Modeling XML import command have been improved. See Importing Mechanical Models and the `import_physmod` command reference in the SimMechanics User's Guide.

- Mates in a CAD assembly (restrictions on the free motion of CAD parts) are now translated into Joint blocks that reflect a particular combination of joint primitives, such as Prismatic, Revolute, Spherical, Bushing, etc. Previously, all degrees of freedom in a CAD assembly were translated into appropriately configured Custom Joint blocks. Rigid connections between parts continue to be translated into Welds.
- Blocks in SimMechanics models generated from Physical Modeling XML files are now, by default, labeled with shorter names. You can change the naming convention in the `import_physmod` command options.

R14SP3

Version: 2.3
New Features: Yes
Bug Fixes: No

New Shared Environment Block

The new Shared Environment block allows you to link two separate SimMechanics block diagrams with a nonphysical connection. The block enforces the same machine environment settings on both machines but adds no mechanical components (bodies or degrees of freedom) to either. Two machines so connected require exactly one Machine Environment block, rather than two.

See the Shared Environment block reference for further details.

Updated Body Spring & Damper Block

The Body Spring & Damper block no longer contains any degrees of freedom.

Previous versions of the Body Spring & Damper block contained six degrees of freedom (DoFs) represented by a Joint. This Joint had to be taken into account when counting DoFs and loops in your model.

The new Body Spring & Damper block instead uses a Shared Environment block to connect the two sides and contains no DoFs. See their respective block references for more information.

Normalizing Rotations

The Body dialog accepts various rotational forms (Euler angles, rotation matrix, quaternion). The Body block now interprets these rotational forms in a slightly different way, so that the standard normalization conditions on rotation matrices and quaternions are consistently enforced. As a result, you might now see slightly different simulation results from earlier versions.

New State Vector Commands

Four new SimMechanics commands allow you to manipulate the mechanical states of your models. See the command references for more.

- `mech_get_states`
- `mech_runtime_states`
- `mech_set_states`
- `mech_transfer_states`

New import_physmod Dialog

The `import_physmod` command generates SimMechanics models from Physical Modeling XML files. In addition to importing Physical Modeling XML through the command line, you can now set up the command through a dialog.

See the `import_physmod` command reference for further information.

Demos Expanded

Two new demos have been added:

- `mech_flexible_four_bar` models a flexible four bar machine.
- `mech_pole_vault` models a rigid pole vaulter, with a discrete event.

The second demo has an associated MAT-file.

Documentation Enhancements

The *SimMechanics User's Guide* has been enhanced.

- The review on representing motion has been revised.
- The analyzing motion has been revised.
- The computer-aided design (CAD) documentation (also available as a separate book) has been significantly revised. See the CAD chapter.
- A new chapter of case studies, based on the Stewart platform, has been added. The studies apply advanced methods and tasks to this system. SimMechanics software includes a related set of demo model and library files.
 - Degrees of freedom, states, closed topology, and constraints
 - Trimming and linearization
 - Designing controllers for the platform
 - Generating code versions of the model
 - Implementing code on dedicated hardware (hardware in the loop)

R14SP2

Version: 2.2.2
New Features: Yes
Bug Fixes: No

Demos Expanded

Two new demos have been added:

- `mech_sticky_box`
- `mech_sticky_screw`

Each demo has an associated MAT-file.

These demos illustrate static friction (stiction) implemented with the Joint Stiction Actuator.

Documentation Enhancements

The online SimMechanics Help has been enhanced with links to four new Web-based AVI animation files (one of them new in this release) that record SimMechanics simulations.

You can access these links most easily by using the Examples index in the Help browser, under **Prerecorded Animations**.