Interfacing Chrono & Matlab
Chrono units for MATLAB and SIMULINK
Chrono::MATLAB
Module for interfacing Chrono and MATLAB
Chrono::MATLAB

• Chrono::MATLAB is a C++ module that enables communication with MATLAB

• Features:
  • call Matlab commands from your C++ program,
  • exchange data to/from Matlab
    • Chrono::Engine C++ matrices are converted to MATLAB,
    • MATLAB variables and matrices are converted to Chrono::Engine C++ matrices
    • use the MATLAB visualization tools, to show simulation data in 2D/3D plots, etc.

• Dependencies:
  • Chrono::Engine main module (required)
  • Chrono::Matlab module
  • MATLAB license
## Code organization

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<td>src/chrono_matlab</td>
<td>main Chrono::MATLAB library implementation</td>
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<td>src/demos/matlab</td>
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Example

• Call MATLAB command(s)

```matlab
// This is the object that you can use to access the Matlab engine.
ChMatlabEngine matlab_engine;

// EXAMPLE 1: execute a Matlab command
matlab_engine.Eval(
    "z=peaks(25); \n    surf(z); \n    colormap(jet); \n    pause(4); \n    ");
```
Example

- Pass a Chrono matrix to MATLAB

```cpp
ChMatrixDynamic<> m_time(30, 1);
ChMatrixDynamic<> m_sine(30, 1);
for (int i = 0; i < 30; i++) {
    m_time(i, 0) = ((double)i / 30.) * 5.;
    m_sine(i, 0) = sin(m_time(i, 0) * 2.);
}
matlab_engine.PutVariable(m_time, "m_time");
matlab_engine.PutVariable(m_sine, "m_sine");
matlab_engine.Eval("figure; plot(m_time,m_sine);");
```
Example

• Pass a MATLAB matrix to Chrono

```matlab
matlab_engine.Eval("m_matr=[0:0.1:5]';");
ChMatrixDynamic<double> m_matr;
matlab_engine.GetVariable(m_matr, "m_matr");
```
Chrono::COSIMULATION

Unit for cosimulation between Chrono and SIMULINK
Chrono::Cosimulation

- Used for interfacing to SIMULINK
- More generally, Chrono::Cosimulation is a C++ module that enables basic cosimulation via TCP/IP sockets

- Features:
  - C++ functions to send/receive datagrams using TCP/IP sockets from Chrono::Engine
  - Can be used to co-simulate with SIMULINK
  - a CEcosimulation.mdl block is provided, to be inserted in your Simulink models as a ready-to-use interface to Chrono::Engine

- Dependencies:
  - Chrono::Engine main module (required)
  - Chrono::Matlab and Chrono::Cosimulation
  - MATLAB & Simulink license
## Code organization

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Background

• Two way co-simulation draws on two simulation tools which simultaneously simulate (advance in time) the two subsystems in which the original system is partitioned.

• Once in a while the two solvers (simulation tools) synchronize to exchange data after which they proceed independently until the next synchronization time.

• TCP/IP sockets are used to exchange data:

• This periodic data synchronization is necessary because the subsystems are coupled. For tightly coupled subsystems the synchronization happens very often.
Background

• A periodic data synchronization is necessary because the subsystems are coupled.
• For tightly coupled subsystems the synchronization must happen very often.
Example

• Co-simulate of a Chrono mechanism with a SIMULINK pneumatic system
Example

• A typical SIMULINK model of a pneumatic system:
Example

- The SIMULINK model with cosimulated load:
Example

• Set parameters in the cosimulation block:
Example

- In Chrono:
  - **receive** one variable from Simulink (the hydraulic cylinder **force**)
  - **send** two variables to Simulink (the hydraulic cylinder **velocity** and **displacement**)

- First we must open a TCP/IP socket:

```cpp
ChSocketFramework socket_tools;

ChCosimulation cosimul_interface(socket_tools,
                                 1, // n.input values from Simulink
                                 2); // n.output values to Simulink

// Prepare the two column vectors of data that will be swapped
ChMatrixDynamic<double> data_in(1, 1);
ChMatrixDynamic<double> data_out(2, 1);

// 4) Wait client (Simulink) to connect...
int PORTNUM = 50009;
cosimul_interface.WaitConnection(PORTNUM);
matlab_engine.Eval("m_matr=[0:0.1:5]'");
```
Example

```cpp
while (true) {
  // A) ----------------- ADVANCE THE Chrono SIMULATION
  if (dt > 0)
    my_system.DoStepDynamics(dt);

  mytime += dt;

  // B) ----------------- SYNCHRONIZATION

  // B.1) - SEND data
  //       * the velocity of the hydraulic actuator
  //       * the displacement of the hydraulic actuator
  data_out(0) = my_link_actuator->GetDist_dt();
  data_out(1) = my_link_actuator->GetDist() - my_link_actuator->Get_SpringRestLength();

  cosimul_interface.SendData(mytime, &data_out); // --> to Simulink

  // B.2) - RECEIVE data
  //        * the force of the hydraulic actuator
  cosimul_interface.ReceiveData(histime, &data_in); // <-- from Simulink

  // - Update the Chrono system with the force value that we received
  my_link_actuator->Set_SpringF(data_in(0));
}
```