Simulation Model of a Twin-Tail, High Performance Airplane

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A mathematical model and associated computer program (fl18bas) to simulate a twin-tailed high performance fighter airplane (McDonnell Douglas F/A-18) are described. The simulation is intended to support advanced control law research for application to high performance aircraft. The modeled flight envelope is extensive, allowing investigations in the high-angle-of-attack portion of the flight regime. Included in the simulation mathematical model are the nonlinear, six degree-of-freedom rigid-body equations, an engine model, and simple sensor and actuator models. A simplified form of the F/A-18 digital control laws (version 8.3.3) is implemented, including only the Auto Flap Up (AFU) flight mode used for air combat maneuvering. Aerodynamic forces and moments are calculated from a wind-tunnel-derived database using table look-ups with linear interpolation. The aerodynamic database has an angle-of-attack range of -10° to +90° and a sideslip range of -20° to +20°. Elastic deformation effects are incorporated in a quasi-static-elastic manner, with no dynamic simulation of the elastic degrees of freedom.
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1. INTRODUCTION

The mathematical model and associated computer program (fl8bas) to simulate a twin-tailed high performance fighter airplane (McDonnell Douglas F/A-18) are described. The simulation is intended to support advanced control law research for application to high performance aircraft. The modeled flight envelope is extensive, allowing investigations in the high-angle-of-attack portion of the flight regime. Included in the simulation mathematical model are the nonlinear, six degree-of-freedom rigid-body equations, an engine model, and simple sensor and actuator models. A simplified form of the F/A-18 digital control laws (version 8.3.3) is implemented, including only the Auto Flap Up (AFU) flight mode used for air combat maneuvering. Aerodynamic forces and moments are calculated from a wind-tunnel-derived database using table look-ups with linear interpolation. The aerodynamic database has an angle-of-attack range of -10° to +90° and a sideslip range of -20° to +20°. Elastic deformation effects are incorporated in a quasi-static-elastic manner, with no dynamic simulation of the elastic degrees of freedom. In the engine model, the throttle-commanded steady-state thrust level and the dynamic response characteristics of the engine are based on airflow rate as determined from a table look-up. Afterburner dynamics are switched in at a threshold based on the engine airflow and commanded thrust. The control surfaces are driven by simple transfer functions with constant rate and position limiting.

1.1 Comments on ACSL

The simulation program written in the Advanced Continuous Simulation Language (ACSL). The ACSL simulation system, described in ACSL (1987), consists of a special purpose high level language, a translator, and various libraries to satisfy the commands available in the language. ACSL functions according to specifications established under the auspices of Simulation Councils, Inc. in 1967 [Format Subcommittee (1967)]. In a typical application of the ACSL system, a simulation model is first constructed using the special ACSL language. A translator is invoked that converts a model written in ACSL to Fortran 77 code. Fortran subroutines can be called from the simulation model with certain restrictions. The Fortran code is compiled and linked with the ACSL libraries. The resulting executable program will prompt for user input and produce plots and printed output.

1.2 Simulation Development History

In 1986, a team was established at the NASA Langley Research Center to address some of the control-related problems of designing highly integrated aircraft. This team was composed of members of the Aircraft Guidance and Control Branch and the Aeroservoelasticity Branch at LaRC and was dubbed the Functional Integration Technology (FIT) team. The focus of the FIT team's effort was highly maneuverable aircraft with minimal structural weight. It was anticipated that such aircraft would require active structural control. The original focus vehicle was the X-29 research airplane. About 6 months after the FIT team was formed, the focus vehicle was changed to the F/A-18. Focusing on an F/A-18 allowed the FIT team to leverage off NASA's High Angle-of-Attack Research Vehicle (HARV) program. Because of the HARV program, NASA would own a preproduction F/A-18 aircraft that would be used in an extensive flight test program. The X-29, on the other hand, was a joint program over which NASA had less control.

One of the first tasks of the FIT team was to develop a simulation of an F/A-18 that incorporated: (1) nonlinear, six degree-of-freedom, rigid body dynamics, (2) linear elastic modes, and (3) unsteady aerodynamics. At that time the team had access to a batch simulation computer program (mdcf18) and documents written by the McDonnell Aircraft Company of the McDonnell Douglas Corporation (MDC) for the F/A-18. The mdcf18 simulation was a complete, nonlinear, six degree-of-freedom batch simulation that ran on a Digital Equipment Corporation VAX computer. The mdcf18 simulation included the 8.3.3 flight control system, hinge-moment calculations, and a
full aerodynamic database. A considerable portion of the mdcf18 simulation was devoted to failure modes of the propulsion and actuation systems. The FIT team also had access to a real-time simulation computer program of an F/A-18 that executed on a CDC Cyber 175 and was written by Unisys personnel for use with the Differential Maneuvering Simulator (DMS) at LaRC. The LaRC-DMS real-time simulation (dmsf18) was derived from the MDC simulation and documents provided by MDC. The FIT team chose to focus on dynamics issues rather than failure modes. There was also a requirement to interface closely with the LaRC real-time facilities and to begin setting up procedures whereby the transfer of specifications and code between researchers and the real-time simulation software development staff could be streamlined. The original FIT F/A-18 simulation [Arbuckle, et al. (1987) and Buttrill, et al. (1987)] was a batch simulation written in ACSL that included 6 nonlinear degrees-of-freedom and 20 elastic degrees-of-freedom, but no control system. The rigid-body aerodynamic model and the engine model of the original FIT F/A-18 simulation were largely derived from the LaRC DMS real-time simulation (dmsf18).

Another research focus at LaRC is agility at high angle-of-attack and low-to-moderate dynamic pressures. To support researchers working in this area, the fully elastic simulation developed by the FIT team was modified. The elastic dynamics were removed. The code that simulated the 8.3.3 flight control software in the LaRC-DMS real-time simulation was obtained and interfaced with the ACSL batch simulation. This report describes the resulting simulation code (fl8bas).

The initial simulation code (fl8bas) developed to support the Aircraft Guidance and Control Branch's high-angle-of-attack research was frozen so that this document could be written. The fl8bas simulation models a preliminary-design version of the thrust-vectoring system proposed for the HARV program. The preliminary-design thrust vectoring system employed two paddles per engine nozzle, whereas the actual system subsequently installed on the HARV demonstrator has three paddles per nozzle. The thrust vectoring capability of the fl8bas simulation will only be described in a limited fashion as required to explain parameter lists. The simulation model without thrust-vectoring can be recovered by setting the logical, LTHVEC, to false.

One outgrowth of the fl8bas simulation was the fl8harv simulation. The fl8harv simulation represents the Aircraft Guidance and Control Branch's best current model of the HARV demonstrator. The mathematical model for fl8harv simulation is documented in a variety of internal memoranda and will be more formally described in a future report.

1.3 Code Development Philosophy

ACSL allows one to call Fortran subroutines from within ACSL source code. Since ACSL source code gets translated into Fortran before compilation, this is not surprising. If one chose, the calculation of all the state derivatives could be done in a Fortran subroutine. The derivatives could be returned as outputs from the subroutine and integrated by ACSL. ACSL could plot and record variables in the parameter list. The equations of motion would then be a black box. Linear analysis on the ACSL-integrated states could be performed. Alternatively, if one had an existing Fortran simulation, the entire Fortran simulation could be made into a subroutine and treated as, from the perspective of ACSL, a discrete process that returned outputs at current time, t, based on inputs at a previous time, t-h. The states of the Fortran subroutine would be hidden from ACSL and none of the linear analysis capability of ACSL could be used.

The goals adopted by the authors for building the simulation were: (1) all integrations arising from continuous processes would result in ACSL-defined states, and (2) the equations of motion, to the extent possible, would be coded in the ACSL language. Goal (2) was compromised slightly in that the calculation of aerodynamic forces and moments and engine steady state performance are done in Fortran subroutines. The authors had available software that greatly facilitated creating code to implement large table look-up type databases characteristic of aerodynamic force and moment.
build-ups and the ACSL capabilities in this area are limited. Since not everyone has ACSL, coding the aerodynamic and engine static models in Fortran served to make major portions of the simulation model more accessible to the research community. The continuous dynamics of the simulation include actuator and sensor dynamics, engine dynamics, and the rigid-body equations of motion. Physically discrete dynamics, such as a digital flight control system, are not coded in ACSL. These dynamics are coded in Fortran subroutines and accessed by the simulation through subroutine calls which occur at discrete time increments using the DISCRETE block feature of ACSL. DISCRETE blocks are explained in the next section (Section 2).
2. SIMULATION STRUCTURE

The general structure of an ACSL simulation is described in section 3 of the ACSL reference manual [ACSL (1987)]. Section 2 of this report summarizes key elements of section 3 of the ACSL manual and will cast the specific structure of this simulation in the context of the discussion and figures of the ACSL reference manual.

ACSL imposes some limitations and programming rigor on its users. ACSL works best when the state derivatives are explicitly defined. If absolutely required, the IMPLICIT operator provided by ACSL can be invoked and the resulting simulation will attempt to solve numerically the implicit formulation, but this would result in unacceptable computing performance in all but the simplest models. Implicit loops are best solved by inserting fast filters or solving them algebraically.

ACSL creates a large common block (ZZCOM) that contains all the simulation variables. Included in ZZCOM are three arrays: the state array, the state derivative array, and the state initial condition array. A state is the output of an integration. A state variable in the state array cannot also be in the state derivative array.

2.1 Overview

The ACSL code structure shown in figure 2.1 is somewhat generic yet also contains the salient features of the F18 simulation. The DYNAMIC...END block of figure 2.1 results in the main simulation loop. The main simulation loop is indicated by the lower shaded box in the overview flow diagram of figure 2.2. In the main loop, if the termination condition, T \geq TSTOP, is not met, the program will integrate forward in time over one communication interval, CINT [ACSL (1987)]. The communication interval determines how often the code in the dynamic block that is not part of either the derivative block or the discrete blocks gets executed. The default value for CINT in the f18bas simulation is 0.025 (1/40) seconds.

The maximum integration step for the DERIVATIVE block is defined by MXSTP in the f18bas simulation and has a default value of 0.00625 (1/160) seconds. The integration algorithm is selected by setting IALG. A variety of integration schemes are offered (IALG = 1 through 7) and are described in ACSL (1987). The default choice for f18bas simulation is IALG=4, a Runge-Kutta second-order method. The Runge-Kutta second-order method was recommended by the author of ACSL for most mechanical systems and has been found to work satisfactorily. No systematic investigation of integration methods has been made for this simulation. Using the Runge-Kutta second-order method, two derivative evaluations are made to advance time over one integration step, MXSTP.

The DISCRETE blocks are executed according to their INTERVAL or SCHEDULE statements. DISCRETE block name1 in figure 2.1 is an example of an interval block that gets executed every Tname seconds. DISCRETE block name2 in figure 2.1 is executed whenever the logical condition defined in its SCHEDULE command becomes true. This type of block might be used to reverse the velocity of a ball bouncing on a table. In the f18bas simulation, the digital control law DISCRETE block, FCS, is an INTERVAL block and is called every TFCS seconds. The default value for TFCS is 0.025 seconds. The choice of a value for TFCS is discussed in section 9 of this report. When different blocks are scheduled for execution at the same time on the event list, such as when a DISCRETE block interval is an even multiple of MXSTP or some other DISCRETE block interval, the order of execution is determined by order of appearance in the model definition code. It is not required that the DISCRETE interval period be a multiple of the maximum integration size for the DERIVATIVE block. An INTERVAL type DISCRETE block sets up a time barrier on an event list. ACSL will shorten the last integration step to insure all simulation variables are synchronized at the correct interrupt time.
PROGRAM
INITIAL
   Includes statements to be executed at time zero after the runtime command "START" has been entered. Values in the the state IC array have not yet been transferred to the state array.
END
DYNAMIC
   DERIVATIVE
      Includes the statements that define the continuous system dynamic model. The elements of the state derivative array, the variables to be integrated, are defined here. A state is the output of an integrator.
      SCHEDULE name2 .XP.var2
END
DISCRETE name1
   INTERVAL Tname = number
      An INTERVAL scheduled DISCRETE includes statements that are executed every Tname seconds.
END
DISCRETE name2
   Includes statements to be executed when the scheduling conditions calculated in the DERIVATIVE block (in this case) for DISCRETE name2 become .true., .i.e. when variable var2 crosses zero in the positive direction.
END
The remainder of the DYNAMIC block includes statements that define auxiliary variables that are required for output only. Those statements are executed every CINT seconds. CINT is the default name for the communication interval.
TERMT(T.GE.TSTOP)
END
TERMINAL
   Includes statements to be executed when the input logical variable to the MACRO TERMT becomes .TRUE.
END
END

Figure 2.1. Outline of Typical ACSL Program

The paths in figure 2.2 associated with the variables LTR, ITFLG, LWRTR and LDBTR arise from code installed to trim the simulation. This path does not arise from any of the typical ACSL constructs found in figure 2.1. The trim logic is discussed in more detail in section 2.2 and figure 2.4 of this report.
From executive

ACSL> START

Call subroutine LOAD. LOAD reads in trim input file, "F18TR", and calls subroutines that initialize aero and engine data arrays stored in common blocks.

ITFLG = 1

Set first pass flag for trim loop.

(1) Set actuator state IC's to control surface position commands determined by the trim search.
(2) Set engine state IC's to commands from trim search. Insures that engines are in steady state at t=0.
(3) Compute steady-state sensor outputs.

TRUE

LFCs

Call F18FCS to execute control law subroutine and generate actuator commands from pilot inputs and sensor data.

Execute DERIVATIVE...END code block.

ITFLG = 2

Call TRIM subroutine to generate next set of trial trim IC's. Return ITFLG to indicate:
(2) trim attempt ongoing (>2) trim ended.

TRUE

Execute various output options according to values of ITFLG, LVDEF, LWRTR and LDBTR

ITFLG ≤ 2

Execute code in DYNAMIC...END block not contained in DERIVATIVE or DISCRETE blocks.

TRUE

Integrate over the communication interval, CINT. Call DERIVATIVE and DISCRETE code blocks as required.

TRUE

Write variables on the OUTPUT and PREPAR lists to units DIS and PRN.

T ≥ TSTP

Execute TERMINAL...END block

Write variables on the OUTPUT and PREPAR lists to units DIS and PRN.

Figure 2.2. Overview of Simulation Flow
Figure 2.3. Initialization and Discrete Block Details
In figure 2.3, two sections of the simulation flow shown in figure 2.2 are expanded. The actions produced by calling subroutine LOAD in the INITIAL...END code block are detailed and the four discrete blocks in the simulation are shown. The discrete blocks that model the flight control system (FCS) and provide a mechanism for making comparisons with flight data (FDT) are invoked by INTERVAL commands. The discrete blocks associated with the engine afterburner models (ABR & ABL) are invoked by SCHEDULE statements.

2.2 Finding a Trim Solution

ACSL has a TRIM command that works with purely continuous models. To use the ACSL TRIM command, a subset of the simulation states (outputs of integrations) is selected using the command

\[
\text{ANALYZ 'CLEAR', 'RELEAS' = \{} \text{state list} \}. 
\]

The ACSL trim function works by adjusting the selected states until their state derivatives are zero. A combination of a Newton step and a steepest descent step is used (section 5.2.4 of ACSL (1987)) to adjust the states. Without some modification, this is not what one generally wants in an airplane trim problem. For example, a simple longitudinal level-flight trim problem might be:

Find,

\[
\{u\} = \{\delta_e, T, \alpha, \theta \}'
\]

such that

\[
\{y\} = \{\alpha, \dot{V}, \dot{q}, \dot{H} \}' = \{0\}
\]

for fixed \(V\) and \(H\), where \(\delta_e, T, \alpha, \theta, V, q\) are elevator deflection, thrust, altitude, angle-of-attack, pitch angle, total airspeed and pitch rate, respectively.

In this case, elevator deflection and thrust are control inputs, and altitude, angle-of-attack, pitch angle, total airspeed and pitch rate are states. Trying to find \(\alpha, V, q\) and \(H\) such that \(\{y\} = \{0\}\) for fixed, arbitrary, values of \(\delta_e, T\) and \(\theta\) is almost always fruitless. To use the ACSL trim capability to solve the trim problem described in equations (2.1) and (2.2), one could add the following equations to the simulation model:

\[
\dot{\delta}_e = k_1 \dot{q} \quad (2.3)
\]

\[
\dot{T} = k_2 \dot{V} + k_3 \dot{H} \quad (2.4)
\]

When attempting to trim, \(k_1, k_2\) and \(k_3\) would be set to something nonzero. The states \(\{\delta_e, T, \alpha, \theta, q\}\) can then be released and the ACSL command "ANALYZ TRIM" invoked. ACSL will then drive \(\{\delta_e, T, \alpha, \theta, q\}\) to zero and in the process, by virtue of equations (2.3) and (2.4), assure that \(\dot{V}, \dot{q}, \dot{H}\) are zero. Equations (2.3) and (2.4) mimic the idea of a trim button or elevator trim-wheel. Generalizing this procedure to handle additional trim cases, such as trimming in a steady level turn or in a symmetric pull-up, could get cumbersome. In addition, it is not clear whether the ACSL trim feature could be made to work with a discrete-block control law in the loop. For these reasons, the authors chose to implement the alternative trimming strategy shown in figure 2.4. The trim strategy employed in fl8bas is not without drawbacks, and a strong case can be made for retaining the ACSL structure and search algorithms as much as possible.
From executive ACSL> START

ITFLG = 1
Set first pass flag for trim loop.

LOAD reads in trim input file, "F18TR", and calls subroutines that initialize aero and engine data arrays stored in common blocks.

(1) Set actuator state IC's to control surface position commands determined by the trim search.
(2) Set engine state IC's to commands from trim search. Insures engines in steady state at t=0.
(3) Compute steady-state sensor outputs.

Y
(...)
Y
(...)

Trim Logic

Trim inner loop that allows implicit loops to settle out. Eq: \( y = f(x,y) \) implicit loops are created when LFCS is engaged.

ITR < ITRMX

TRUE

LFCU

TRUE

Call F18FCU to execute control law subroutine and generate actuator commands from pilot inputs and sensor data.

LTR and (ITFLG < 2)

T > TSTP

TRUE

Execute code in DYNAMIC..END block not contained in DERIVATIVE or DISCRETE blocks.

Integrate over the communication interval, CINT. Call DERIVATIVE and DISCRETE code blocks as required.

Write variables on the OUTPUT and PREPAR lists to units DIS and PRN.

Execute TERMINAL..END block

Write variables on the OUTPUT and PREPAR lists to units DIS and PRN.

Return to ACSL executive: ACSL>

Figure 2.4. Trim loop expanded.
Details of the logic used to trim the simulation are shown in figure 2.4. Subroutine TRIM defines an array called XTRIM and an array called YTRIM. The first NXTR elements of XTRIM are varied until the first NXTR elements of YTRIM are within some tolerance of zero. The allowable elements of XTRIM and YTRIM are shown in tables 2.1 and 2.2, respectively.

Table 2.1. Selectable members of XTRIM array

<p>| | | |</p>
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<thead>
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<tbody>
<tr>
<td>1</td>
<td>MACHTR</td>
<td>Mach number, n.d.</td>
</tr>
<tr>
<td>2</td>
<td>BETTR</td>
<td>sideslip angle, ( \beta ), radians</td>
</tr>
<tr>
<td>3</td>
<td>ALFTR</td>
<td>angle of attack, ( \alpha ), radians</td>
</tr>
<tr>
<td>4</td>
<td>PIC</td>
<td>body axis roll rate, rad/sec</td>
</tr>
<tr>
<td>5</td>
<td>QIC</td>
<td>body axis pitch rate, rad/sec</td>
</tr>
<tr>
<td>6</td>
<td>RIC</td>
<td>body axis yaw rate, rad/sec</td>
</tr>
<tr>
<td>7</td>
<td>THETR</td>
<td>Euler pitch angle, radians</td>
</tr>
<tr>
<td>8</td>
<td>PHITR</td>
<td>Euler roll angle, radians</td>
</tr>
<tr>
<td>9</td>
<td>PSITR</td>
<td>Euler heading angle, radians</td>
</tr>
<tr>
<td>10</td>
<td>GAMTR</td>
<td>longitudinal flight path angle, ( \gamma ), radians</td>
</tr>
<tr>
<td>11</td>
<td>DTVL</td>
<td>left engine thrust vectoring nozzle deflection, degrees</td>
</tr>
<tr>
<td>12</td>
<td>DTVR</td>
<td>right engine thrust vectoring nozzle deflection, degrees</td>
</tr>
<tr>
<td>13</td>
<td>PCATR</td>
<td>lateral stick deflection (pilot commanded aileron), inches</td>
</tr>
<tr>
<td>14</td>
<td>PCSTR</td>
<td>longitudinal stick deflection (pilot commanded stabilator), inches</td>
</tr>
<tr>
<td>15</td>
<td>PCRTR</td>
<td>rudder pedal force (pilot commanded rudder), lbs</td>
</tr>
<tr>
<td>16</td>
<td>DPSYTR</td>
<td>throttle position, symmetric, [31,127]</td>
</tr>
<tr>
<td>17</td>
<td>DPASTR</td>
<td>throttle position, antisymmetric, [96,96]</td>
</tr>
<tr>
<td>18</td>
<td>DSSYTR</td>
<td>stabilator position, symmetric, degrees</td>
</tr>
<tr>
<td>19</td>
<td>DSASTR</td>
<td>stabilator position, antisymmetric, degrees</td>
</tr>
<tr>
<td>20</td>
<td>DASYTR</td>
<td>aileron position, symmetric, degrees</td>
</tr>
<tr>
<td>21</td>
<td>DAASTR</td>
<td>aileron position, antisymmetric, degrees</td>
</tr>
<tr>
<td>22</td>
<td>DRSYTR</td>
<td>rudder position, symmetric (both t.e. in), degrees</td>
</tr>
<tr>
<td>23</td>
<td>DRASTR</td>
<td>rudder position, antisymmetric (both t.e. left), degrees</td>
</tr>
<tr>
<td>24</td>
<td>DNSYTR</td>
<td>leading-edge flap position, symmetric, degrees</td>
</tr>
<tr>
<td>25</td>
<td>DNASTR</td>
<td>leading-edge flap position, antisymmetric, degrees</td>
</tr>
<tr>
<td>26</td>
<td>DFSYTR</td>
<td>trailing-edge flap position, symmetric, degrees</td>
</tr>
<tr>
<td>27</td>
<td>DFASTR</td>
<td>trailing-edge flap position, antisymmetric, degrees</td>
</tr>
<tr>
<td>28</td>
<td>CSB</td>
<td>commanded speed brake, degrees</td>
</tr>
<tr>
<td>29</td>
<td>MUDGTR</td>
<td>bank angle, ( \mu ), degrees</td>
</tr>
<tr>
<td>30</td>
<td></td>
<td>open for future expansion</td>
</tr>
</tbody>
</table>
Table 2.2. Selectable members of YTRIM array

<p>| | |</p>
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>UD</td>
</tr>
<tr>
<td>2</td>
<td>VD</td>
</tr>
<tr>
<td>3</td>
<td>WD</td>
</tr>
<tr>
<td>4</td>
<td>PD</td>
</tr>
<tr>
<td>5</td>
<td>QD</td>
</tr>
<tr>
<td>6</td>
<td>RD</td>
</tr>
<tr>
<td>7</td>
<td>GAMZ</td>
</tr>
<tr>
<td>8</td>
<td>PHIZ</td>
</tr>
<tr>
<td>9</td>
<td>THE</td>
</tr>
<tr>
<td>10</td>
<td>LAMBDA</td>
</tr>
<tr>
<td>11</td>
<td>FVRA(2)</td>
</tr>
<tr>
<td>12</td>
<td>CLERR</td>
</tr>
<tr>
<td>13</td>
<td>CMRFSF</td>
</tr>
<tr>
<td>14,15</td>
<td>open for future expansion</td>
</tr>
</tbody>
</table>

The elements of XTRIM and YTRIM are selected by setting the first \( NXTR \) elements of the IXSEL and IYSEL arrays. A typical \( 4 \times 4 \) longitudinal open-loop trim case could be set up as indicated in figure 2.5. In this example, Mach and altitude are selected a priori and the variables \( \{ \alpha, \theta, \delta_{SSy}, \text{power setting} \} \) are varied until \( \{ \dot{u}, \dot{w}, \dot{q}, \gamma - \gamma_T \} \) are driven to zero.

ACSL>

ACSL> \( NXTR = 4 \)
ACSL> HIC=10000., MACHTR=.5, GAMTR=0.0, LFCS=.F.
ACSL> IXSEL=3,7,16,18
ACSL> IYSEL=1,3,5,7
ACSL> START

Figure 2.5. Trim example 1

Trim example 2 in figure 2.6 is similar except that a trim with the flight control system engaged is sought. The pilot longitudinal stick command is substituted for stabilator position in the list of variables to be varied.

ACSL>

ACSL> \( NXTR = 4 \)
ACSL> MACHTR=.5, GAMTR=0.0, LFCS=.T.
ACSL> IXSEL=3,7,16,14
ACSL> IYSEL=1,3,5,7
ACSL> START

Figure 2.6. Trim example 2

Achieving trim requires that all state derivatives are zero, not just the states associated with aircraft motion. The states associated with actuator, sensor, and control law dynamics must be trimmed. For the continuous actuator and sensor states, one approach would be to include these additional states explicitly in the nonlinear trim problem. This would serve to unnecessarily increase the dimension of the trim search. In addition, the trim architecture would become dependent on actuator and sensor transfer functions. For the transfer-function-based dynamics typically associated with actuator and sensors, the calculation of the required state initial conditions to achieve trim for a given input is simple. Therefore, when in the trim loop, the dynamics of the actuator,
sensor, and control system are trimmed locally, not as part of the nonlinear search. Integrators are turned off and steady state values for all filters are calculated and passed through. Actuator and sensor state initial conditions are set so that the state derivatives are zero for the given inputs. However, local trimming of actuator and sensor dynamics creates an implicit loop in the global trim problem when the flight control system is engaged (LFCS set true - see section 9.2). For example, suppose trim pitch stick position (PCSTR) is one of the admissible XTRIM variables. A change in PCSTR produces a change in the control surface commands, which instantaneously produces (since the actuator dynamics are suppressed) a new control deflection. The change in control deflection produces a change in the vertical accelerometer output, nzs. Since nzs is a feedback, a change in nzs produces an additional change in the control surfaces, which produces new, slightly different nzs. The trim search assumes the following functional relationship:

\[ Y_{TRIM} = f(X_{TRIM}) \]

The effect of the implicit loop is to make \( Y_{TRIM} \) dependent not only on \( X_{TRIM} \), but on the past values of \( Y_{TRIM} \). The degradation the functional relationship will impede or prevent convergence.

The somewhat ad hoc solution adopted by the authors was to implement an inner trim loop to converge the implicit loop (see figure 2.4). The inner loop increments a counter, ITR. The program loops through the control and flight dynamics code with constant trim driver and initial conditions values until ITR = ITRMX. The default value for ITRMX is 6.

Subroutine TRIM is called after the inner trim loop completes ITRMX passes. The trim routine perturbs the control commands and flight states specified for XTRIM and checks for convergence of the YTRIM values. When convergence is achieved, ITFLG is set to 3. If convergence fails, either because the maximum outer iteration count (MXITR) is exceeded or the sensitivity matrix becomes singular, ITFLG is set to 4. ITFLG will be set back to 1 at the first pass of each run (as shown in figure 2.4), and trimming will occur each time the program is started at the ACSL prompt, unless the variable LTR is set false. If LTR is false, the program will pass once through the initial section and go directly into the main program loop, bypassing the trim loop.

Trim convergence is determined in the ACTRML subroutine, which is called from the TRIM subroutine. The variable TRTOL (default = 0.00005) sets the tolerance criterion for convergence.
3. MASS AND GEOMETRY DATA

3.1 General Arrangement

The general arrangement of a single place F/A-18 is depicted in figure 3.1. This report and the MDC documents listed in the References locate points on the airframe using fuselage station (FS), buttock line (BL), and water line (WL) coordinates. The (FS, BL, WL) coordinates are defined in table 3.1. At the plane of symmetry, the BL coordinate is zero.

<table>
<thead>
<tr>
<th>Table 3.1. (FS, BL, WL) coordinates of figure 3.1</th>
</tr>
</thead>
<tbody>
<tr>
<td>FS</td>
</tr>
<tr>
<td>BL</td>
</tr>
<tr>
<td>WL</td>
</tr>
</tbody>
</table>

The F/A-18 is a single place, mid-wing, high performance twin engine fighter capable of carrying a variety of armament loadings. For the F/A-18, the primary mission is that of "Fighter Escort". The Fighter Escort mission loading is two wingtip mounted Sidewinder missiles, two fuselage mounted Sparrow missiles, and the M61A1 gun. Each engine is a General Electric, F404-GE-400 rated at 16,100 lbs of uninstalled, static, sea level thrust. The total internal fuel capacity is 10,860 lbs while 6,732 lbs of fuel can be carried in external tanks. The design load factors are +7.5/-3.0 g's. The design sinking speed at touchdown is 25.1 ft/sec.

A moderately swept wing and a highly swept leading-edge extension (LEX) form the primary lifting surface. Leading-edge and trailing-edge flaps on the wing are used for carrier operations, subsonic maneuvering, and cruise. The flap deflections are scheduled with Mach number and angle of attack to provide improved drag and stability characteristics. All moving horizontal tail surfaces are mounted behind and below the wing to provide positive stability at high angles of attack. Twin vertical fins are both canted out and toed out (figure 3.1).

Pitch control is provided by the horizontal tails. Lateral control is accomplished with a blend of ailerons, differential flaps, and differential horizontal tail. Directional control is provided by a rudder on each vertical fin. A speedbrake is also available for deceleration control in the maneuvering configuration. [MDC A7247, p2-1]

3.2 Sign Conventions

While the (FS, BL, WL) coordinate system is used in various MDC reports and the MDC simulation to locate positions on the aircraft, the equations of motion make use of a right-hand body-fixed frame aligned with the (FS, BL, WL) and typically called the body frame. The body frame origin is at the center-of-gravity (c.g.) of the aircraft and is oriented so that \( X_B \) is positive forward, \( Y_B \) is positive out the right wing, and \( Z_B \) is positive down. For example, a sensor package that is located at \( (FS_\sigma, BL_\sigma, WL_\sigma) \) would have the following coordinates in the body frame,

\[
\begin{align*}
X_B & = -(FS_\sigma - FS_{cg}) \\
Y_B & = -(BL_\sigma - BL_{cg}) \\
Z_B & = -(WL_\sigma - WL_{cg})
\end{align*}
\]

where \( (FS_{cg}, BL_{cg}, WL_{cg}) \) are the coordinates of the c.g. in the (FS, BL, WL) axes system.
The body frame, along with the stability frame, control surface sign conventions, and coefficient sign conventions, is depicted in figure 3.2. The stability frame is denoted by the subscript "S" in 3.2. A rotation of \( \alpha \) of the stability frame about the \( Y_S \) axis brings the stability and body frames into alignment. The roll, pitch and yaw aerodynamic moment coefficients, \( C_1, C_m \) and \( C_n \), are defined about body frame axes, \( X_B, Y_B, \) and \( Z_B \), respectively. The lift, drag, and side force coefficients, \( C_L, C_D \) and \( C_Y \), are defined as positive along the \(-Z_S\) axis, the \(-X_S\) axis and the \(+Y_S\) axis, respectively. Note that \( Y_S \) is aligned with \( Y_B \).

![Figure 3.2. Axis System and Sign Convention](image_url)

The control surface sign conventions, depicted in figure 3.2, apply to each member of a control surface pair and are described in table 3.2.

| \( \delta_n \) | leading-edge flap | positive leading edge down |
| \( \delta_f \) | trailing-edge flap | positive trailing edge down |
| \( \delta_A \) | aileron | positive trailing edge down |
| \( \delta_H \) | horizontal tail | positive trailing edge down |
| \( \delta_R \) | rudder | positive trailing edge left |
### 3.3 Dimensional Data

The airplane component dimensional data are given in table 3.2 and pages 2.6-2.8 of MDC report A7247, vol I.

#### Table 3.3 Airplane Dimensional Data

<table>
<thead>
<tr>
<th>Total Airplane</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Net Wetted Area (minus engine nozzles)</td>
<td>2028 ft²</td>
</tr>
<tr>
<td>Overall length</td>
<td>56.0 ft</td>
</tr>
<tr>
<td>Overall Height</td>
<td>15.3 ft</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Wing</th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Area, ( S_{\text{REF}} )</td>
<td>400 ft²</td>
</tr>
<tr>
<td>Area (Actual)</td>
<td>401.7 ft²</td>
</tr>
<tr>
<td>Wetted Area (Including launchers and aileron actuator fairings)</td>
<td>562 ft²</td>
</tr>
<tr>
<td>Span, ( b_{\text{REF}} )</td>
<td>37.42 ft</td>
</tr>
<tr>
<td>Aspect ratio, ( AR )</td>
<td>3.5</td>
</tr>
<tr>
<td>Chords</td>
<td></td>
</tr>
<tr>
<td>Root Chord (Theoretical)</td>
<td>15.86 ft</td>
</tr>
<tr>
<td>Root Chord (Exposed @ ( X_W ) 54.0)</td>
<td>13.19 ft</td>
</tr>
<tr>
<td>Tip Chord</td>
<td>5.52 ft</td>
</tr>
<tr>
<td>MAC, ( \zeta_{\text{REF}} )</td>
<td>11.52 ft</td>
</tr>
<tr>
<td>Leading Edge (L.E.) Sweep</td>
<td>26.7°</td>
</tr>
<tr>
<td>( \zeta/4 ) Sweep</td>
<td>20°</td>
</tr>
<tr>
<td>Taper Ratio</td>
<td>0.35</td>
</tr>
<tr>
<td>Dihedral</td>
<td>-3°</td>
</tr>
<tr>
<td>Geometric Twist</td>
<td>0.0° at ( X_W ) 145.39</td>
</tr>
<tr>
<td></td>
<td>4.0° L.E. down at tip</td>
</tr>
<tr>
<td></td>
<td>0.0°</td>
</tr>
<tr>
<td>Incidence</td>
<td>Modified NACA 65A with sharp L.E.</td>
</tr>
<tr>
<td>Airfoil Section</td>
<td></td>
</tr>
<tr>
<td>Airfoil Thickness at ( X_W ) 56.876</td>
<td>5.0 % chord</td>
</tr>
<tr>
<td>( X_W ) 145.390</td>
<td>3.5 % chord</td>
</tr>
<tr>
<td>Tip Chord</td>
<td>3.5 % chord</td>
</tr>
</tbody>
</table>

| Leading-Edge Flaps                     |                  |
| Type                                   | Plain            |
| Area                                   | 48.4 ft² total   |
| Span                                   | 13.8 ft per side |
| Deflection (+ leading edge down)       | \([0.0°, 34°]*\), maneuvering |
|                                       | \([12°, 34°]*\), Takeoff and Landing |
|                                       | \(\pm 3°\) differential |

| Trailing-Edge Flaps                    |                  |
| Type                                   | Single Slotted w/Drooped Shroud |
| Area                                   | 61.9 ft² total   |
| Span                                   | 8.72 ft per side |
| Wing Span Range Covered (percent)      | 19-68.6 % \( b/2 \) |
| Chord                                  | 30 % c           |
| Deflections (+ trailing edge down)     | \([+17°, +30°]*\), Takeoff |
|                                       | \([+17°, +45°]*\), Landing |
Table 3.3  Airplane Dimensional Data (continued)

<table>
<thead>
<tr>
<th>Section</th>
<th>Description</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>Shroud</td>
<td>Area</td>
<td>13.9 ft² total</td>
</tr>
<tr>
<td></td>
<td>Chord</td>
<td>7 % c</td>
</tr>
<tr>
<td></td>
<td>Hinge Line</td>
<td>68.5 % c</td>
</tr>
<tr>
<td></td>
<td>Deflection (+ down)</td>
<td>[-10°, +30°]</td>
</tr>
<tr>
<td>Ailerons</td>
<td>Type</td>
<td>Single Slotted w/ Drooped Shroud</td>
</tr>
<tr>
<td></td>
<td>Area</td>
<td>24.4 ft² total</td>
</tr>
<tr>
<td></td>
<td>Span</td>
<td>5.68 ft per side</td>
</tr>
<tr>
<td></td>
<td>Percent Wing Span</td>
<td>68.8 -100% b/2</td>
</tr>
<tr>
<td></td>
<td>Deflections (+ trailing edge down)</td>
<td>[-25°, +45°], Takeoff and Landing [-25°, +25°], Maneuvering</td>
</tr>
<tr>
<td>Shroud</td>
<td>Area</td>
<td>5.6 ft² total</td>
</tr>
<tr>
<td></td>
<td>Chord</td>
<td>7 % c</td>
</tr>
<tr>
<td></td>
<td>Hinge Line</td>
<td>68.5 % c</td>
</tr>
<tr>
<td></td>
<td>Deflection (+ down)</td>
<td>[-10°, +30°]</td>
</tr>
<tr>
<td>Leading Edge Extension (LEX)</td>
<td>Planform Area (Slots Closed)</td>
<td>56.0 ft²</td>
</tr>
<tr>
<td></td>
<td>Wetted Area</td>
<td>210.0 ft²</td>
</tr>
<tr>
<td></td>
<td>Leading Edge Sweep</td>
<td>43°</td>
</tr>
<tr>
<td></td>
<td>Incidence (forward of inlet)</td>
<td>6°</td>
</tr>
<tr>
<td></td>
<td>LEX Intersection with Wing</td>
<td>F.S. 403.9</td>
</tr>
<tr>
<td></td>
<td></td>
<td>B.L. 54.0</td>
</tr>
<tr>
<td></td>
<td></td>
<td>W.L. 108.2</td>
</tr>
<tr>
<td>Horizontal Tails</td>
<td>Exposed Area</td>
<td>88.1 ft²</td>
</tr>
<tr>
<td></td>
<td>Wetted Area</td>
<td>176.0 ft²</td>
</tr>
<tr>
<td></td>
<td>Aspect Ratio</td>
<td>2.4</td>
</tr>
<tr>
<td></td>
<td>Taper Ratio</td>
<td>.46</td>
</tr>
<tr>
<td></td>
<td>L.E. Sweep</td>
<td>47.2°</td>
</tr>
<tr>
<td></td>
<td>c/4 Sweep</td>
<td>42.8°</td>
</tr>
<tr>
<td></td>
<td>Dihedral</td>
<td>-2°</td>
</tr>
<tr>
<td></td>
<td>Span, b_REF</td>
<td>14.67 ft</td>
</tr>
<tr>
<td></td>
<td>Total Span</td>
<td>21.6 ft</td>
</tr>
<tr>
<td>Chords</td>
<td>Root Chord (Exposed)</td>
<td>8.23 ft</td>
</tr>
<tr>
<td></td>
<td>Tip Chord</td>
<td>3.79 ft</td>
</tr>
<tr>
<td></td>
<td>MAC, c_HT</td>
<td>6.28 ft</td>
</tr>
<tr>
<td></td>
<td>Tail length (c/4 to c_HT/4)</td>
<td>16.81 ft</td>
</tr>
<tr>
<td></td>
<td>Airfoil section</td>
<td>Modified NACA 65A with Sharp L.E.</td>
</tr>
<tr>
<td></td>
<td>Airfoil Thickness at Root</td>
<td>6 % c_HT</td>
</tr>
<tr>
<td></td>
<td>Tip</td>
<td>2 % c_HT</td>
</tr>
<tr>
<td></td>
<td>Hinge Line</td>
<td>13 % c_HT</td>
</tr>
</tbody>
</table>
### Table 3.3  Airplane Dimensional Data (concluded)

**Horizontal Tails (continued)**

| Deflections (± trailing edge down) |  
|-------------------------------|---------------------------------------------------------------|
| [-24°, +8°], Symmetric         | [-24°, +10.5°], Max                                          |

**Vertical Tails**

| Area                          | 52.0 ft² each |
| W wetted Area                 | 104.0 ft² each |
| Aspect Ratio                  | 1.2           |
| Taper Ratio                   | 0.4           |
| L.E. Sweep                    | 41.3°         |
| c/4 Sweep                     | 35.0°         |
| Cant (Tip out)                | 20° out       |
| Toe Out                       | 1°            |
| Panel Span                    | 7.92 ft       |

**Chords**

| Root Chord (Exposed)          | 9.42 ft       |
| Tip Chord                     | 3.75 ft       |
| MAC, \( \tilde{c}_{VT} \)     | 6.99 ft       |

**Tail length (\( \tilde{c}/4 \) to \( \tilde{c}_{VT}/4 \))**

| 10.18 ft                     |

**Airfoil section**

| Modified NACA 65A with Sharp L.E. |

**Airfoil Thickness at**

| Root                         | 5 % \( \tilde{c}_{VT} \) |
| Tip                          | 3 % \( \tilde{c}_{VT} \) |

**Rudders**

| Area                          | 7.72 ft² each |
| Span                         | 5.21 ft       |
| Percent Chord                | 20 % c        |
| Deflection                   | ± 30°         |

**Fuselage**

| Length                        | 53 ft         |
| Maximum Width                 | 7.6 ft        |
| Wetted Area (includes nacelles, canopy, and nozzles) | 890 ft² |

**Speedbrake**

| Planform Area                 | 13.9 ft²      |
| Span                          | 2.5 ft        |
| Chord                         | 5.57 ft       |
| Maximum Deflection (relative to ML) | 60°  |
3.4 Aerodynamic Reference Dimensions

The aerodynamic reference dimensions are given in table 3.4 below and in MDC report A7247, page 3-2.

Table 3.4. Aerodynamic Reference Dimensions

<p>| | |</p>
<table>
<thead>
<tr>
<th></th>
<th></th>
</tr>
</thead>
<tbody>
<tr>
<td>Wing Area, $S_{REF}$</td>
<td>400 ft$^2$</td>
</tr>
<tr>
<td>Wing MAC, $c_{REF}$ (L.E.MAC @ FS 423.99)</td>
<td>138.275 in = 11.523 ft</td>
</tr>
<tr>
<td>Wing Span, $b_{REF}$</td>
<td>37.42 ft</td>
</tr>
<tr>
<td>Horizontal Tail Moment Arm, $l_{HT}$ ($c/4$ to $c_{HT}/4$)</td>
<td>201.76 in</td>
</tr>
<tr>
<td>Horizontal Tail Volume Coefficient, $V_{HT}$</td>
<td>.321</td>
</tr>
<tr>
<td>Vertical Tail Moment Arm, $l_{VT}$ ($c/4$ to $c_{VT}/4$)</td>
<td>122.1 in</td>
</tr>
<tr>
<td>Vertical Tail Volume Coefficient, $V_{VT}$</td>
<td>.0707</td>
</tr>
</tbody>
</table>

3.5 Weight, Center of Gravity, and Inertia Data

The weight, center-of-gravity location, and mass distribution data for the default simulation configuration and for a fighter escort configuration are shown in Table 3.5. The fighter escort description, along with several others, is found in figure 2.3-1 of MDC report A7247. The default configuration represents an early estimate of an F18 HARV configuration after the addition of thrust vectoring hardware. Of all the configurations listed in figure 2.3-1 of MDC report A7247, the data for the fighter escort configuration with 60 percent internal fuel most closely matches the default values.

Table 3.5. Summary of Simulation Weight, Center-of-Gravity, and Inertia

<table>
<thead>
<tr>
<th></th>
<th>Weight (lbs)</th>
<th>c.g. Locations</th>
<th>Moments and Products of Inertia</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>FS (in)</td>
<td>WL (ft$^2$)</td>
<td>$I_{xx}$</td>
</tr>
<tr>
<td>Default</td>
<td>33310</td>
<td>455.0</td>
<td>102.8</td>
</tr>
<tr>
<td>Fighter Escort</td>
<td>31665</td>
<td>457.3</td>
<td>101.6</td>
</tr>
</tbody>
</table>

(60% internal fuel)

The $I_{xz}$ product of inertia in table 3.5 is defined as the integral over the volume of the aircraft of the product $(xz)$ (body frame coordinates) weighted with the mass density, $\sigma$, of the aircraft. The negative of this quantity is what appears as the $(1,3)$ and $(3,1)$ elements of inertia matrix. Thus,

$$I_{xz} = \iiint \sigma xz \, dV$$

(3.2)

The product $I_{xz}$ is typically positive for aircraft with vertical fins but is negative in this case.
4. EQUATIONS OF MOTION

The derivation of the equations governing the motion of a rigid airplane over a flat, nonrotating Earth has been performed many times in the literature and is not likely to be improved upon here. Readers interested in the derivation of said equations are referred to Etkin (1972) and Roskam (1979). In the fl8bas simulation, mass and inertia properties are constants and do not vary with time. If desired, the mass and inertias could be made functions of fuel load according to data presented in MDC-A7247 and MDC-A8575. Gravity is assumed to be aligned with the +Z axis of a local (Earth) right-handed reference frame fixed at sea level. Gravity is assumed constant over the airplane volume, which results in gravity acting as a force at the center of mass and producing no moments. In fact, gravity is constant with altitude with the default value being the sea level value. A reference frame fixed to the body of the airplane (body frame) is the most convenient for expressing the applied aerodynamic and thrust loads. As indicated in figure 3.2, the body frame origin is at the center of gravity and the frame is oriented so that +X_B is out the nose, +Y_B is out the right wing, and +Z_B is out the belly. The airplane is assumed symmetric about the plane formed by the X_B and Z_B axes, so that the I_{xy} and the I_{yz} products of inertia are zero and are not included in the simulation equations.

4.1 Translational Equations

Let the translational inertial velocity of the airplane expressed in body frame components be given by \([u,v,w]'\) and the rotational inertial velocity of the airplane in body frame components be given by \([p,q,r]'\). The equations governing translational motion can then be written as,

\[
\begin{bmatrix}
0 & -r & q \\
-\frac{r}{m} & 0 & -\frac{q}{m} \\
\frac{q}{m} & \frac{r}{m} & -\frac{1}{m}
\end{bmatrix}
\begin{bmatrix}
u \\
v \\
w
\end{bmatrix}
=\begin{bmatrix}
F_x \\
F_y \\
F_z
\end{bmatrix}_G + \begin{bmatrix}
F_x \\
F_y \\
F_z
\end{bmatrix}_A + \begin{bmatrix}
F_x \\
F_y \\
F_z
\end{bmatrix}_E
\]

where the subscripts "G", "A", and "E" denote gravitational, aerodynamic and thrust-induced forces. The components of the gravitational force are given by,

\[
\begin{bmatrix}
F_x \\
F_y \\
F_z
\end{bmatrix}_G = -mg\begin{bmatrix}l_{xz} \\
l_{yz} \\
l_{zz}
\end{bmatrix}_G = mg\begin{bmatrix}-\sin(\theta) \\
\cos(\theta)\sin(\phi) \\
\cos(\theta)\cos(\phi)
\end{bmatrix}
\]

(4.2)

where \([l_{xz} l_{yz} l_{zz}]'\) is the third column of the direction cosine matrix describing a transformation from local frame to body frame components and \(\theta\) and \(\phi\) are the Euler pitch and roll angles, respectively. The aerodynamic force components are given by,
\[
\begin{pmatrix}
F_x \\
F_y \\
F_z
\end{pmatrix}
_A = \tilde{q}S
\begin{pmatrix}
C_x \\
C_y \\
C_z
\end{pmatrix}
\] (4.3)

The thrust-induced forces are defined in equations (6.8) of section 6.

### 4.2 Rotational Equations

The body frame rotational equations can be written in a form identical to equation (4.1), with the understanding that moments due to gravity are zero,

\[
\begin{pmatrix}
I_x & 0 & -I_{xz} \\
0 & I_y & 0 \\
-I_{xz} & 0 & I_z
\end{pmatrix}
\begin{pmatrix}
p \\
q \\
r
\end{pmatrix}
+ \begin{pmatrix}
0 & r & q \\
r & 0 & -p \\
-q & p & 0
\end{pmatrix}
\begin{pmatrix}
I_x & 0 & -I_{xz} \\
0 & I_y & 0 \\
-I_{xz} & 0 & I_z
\end{pmatrix}
\begin{pmatrix}
p \\
q \\
r
\end{pmatrix}
\]

\[
= \begin{pmatrix}
M_x \\
M_y \\
M_z
\end{pmatrix}
_G + \begin{pmatrix}
M_x \\
M_y \\
M_z
\end{pmatrix}
_A + \begin{pmatrix}
M_x \\
M_y \\
M_z
\end{pmatrix}
_E
\] (4.4)

and where the aerodynamic moments are given by,

\[
\begin{pmatrix}
M_x \\
M_y \\
M_z
\end{pmatrix}
_A = \tilde{q}S
\begin{pmatrix}
b \\
c_1 \\
c_m \\
b \\
c_n
\end{pmatrix}
\] (4.5)

The thrust-induced moments are defined in equations (6.10) of section 6.

### 4.3 Combined Accelerations

If the body frame components of translational and rotational velocity are combined into a 6x1 generalized velocity vector,

\[
\{V\} = \begin{pmatrix}
u \\
v \\
w \\
p \\
q \\
r
\end{pmatrix}
\] (4.6)

then equations (4.1) and (4.2) can be combined and written as,

\[
[M]_I \dot{\{V\}} + [\Omega][M]_I\{V\} = \{F\}_G + \{F\}_A + \{F\}_E
\] (4.7)

where the inertial mass is given by,
and the matrix representing body frame rotation is,

\[
[\Omega] = \begin{bmatrix}
0 & -r & q & 0 & 0 & 0 \\
r & 0 & -p & 0 & 0 & 0 \\
-q & p & 0 & 0 & 0 & 0 \\
0 & 0 & 0 & -r & q & 0 \\
0 & 0 & 0 & r & 0 & -p \\
0 & 0 & 0 & -q & p & 0
\end{bmatrix}
\]

(4.9)

In order to achieve an explicit definition of the airplane accelerations, equation (4.7) must be modified. Observe that the time rate-of-change of angle of attack in still air, given by,

\[
\dot{\alpha} = \frac{uw - wu}{u^2 + w^2}
\]

is clearly a function of body frame accelerations. In the F/A-18 aerodynamic build-up, as is the case for almost all such aerodynamic models, the coefficients of lift and pitch contain contributions by a nondimensionalized form of the angle-of-attack rate-of-change

\[
C_X = \ldots + C_{X_{\alpha}} \left( \frac{\dot{\alpha} \dot{\alpha}^T}{2V} \right)
\]

(4.11)

where the symbol 'X' in equation (4.11) can be replaced by 'L' (lift) or 'm' (pitch). In the F/A-18 simulation, \(C_{X_{\alpha}}\) is a function of Mach, altitude, and angle-of-attack. The implication of equations (4.10) and (4.11) is that the generalized aerodynamic force column vector appearing in equation (4.7) should be written as,

\[
\{F\}_A = \{F\}_A \bigg|_{\{V\} = 0} - \{M\}_A \dot{\{V\}}
\]

(4.12)

where,
\[ [M]_A = -\frac{\partial[F]}{\partial[V]} \]  

(4.13)

\([M]_A\) represents an increment to the inertial mass matrix of equation (4.7). If we further define a generalized inertial force as,

\[ \{F\}_I = -[\Omega]\{M\}_I[V] \]  

(4.14)

and combine equations (4.7), (4.12) and (4.14), we get the equations of motion as implemented in the simulation,

\[ \dot{[M]}[V] = \{F\}_{I+G+A+E} \]  

(4.15)

where the total mass matrix is:

\[ [M] = [M]_I + [M]_A \]  

(4.16)

Equation (4.15) must be solved each simulation time step for the unknown accelerations in \([V]\). Recall \([V] = [u,v,w,p,q,r]\) (equation 4.6). If the mass matrix, \([M]\), were constant, then the inverse, \([M]\)^{-1}, could be formed at time zero and a simple left multiplication of the right-hand-side forces by \([M]\)^{-1} would produce the accelerations. The aerodynamic part of the mass matrix, \([M]_A\), is a function of angle of attack, Mach number, altitude, and dynamic pressure and is therefore time-varying. Forming the inverse of \([M]\) each time step would be prohibitive. The approach used in the simulation documented in this report is to solve (4.15) using Gaussian elimination. In a typical application of Gaussian elimination, row and column switching (pivoting) is performed to insure that the largest possible elements are used as divisors. Both partial and full pivoting strategies exist. In a general application, if the diagonal elements are used as divisors without pivoting, the divisors may become zero. For most airplanes, and for any configuration of the F/A-18, the inertial mass matrix, \([M]_I\), is sufficiently diagonally dominant and \([M]_A\) is sufficiently small throughout the flight envelope, that the diagonal elements of \([M]\) can be used as divisors with impunity. A custom 6x6 equation solver that employs no pivoting strategy is used in the simulation to solve (4.15). The custom solver is implemented in subroutine XRBVDC. In order to improve efficiency, the use of DO-LOOPS in XRBVDC was minimized. The simulation was tested using both the custom solver and a general purpose subroutine that employed a full pivoting strategy (the most robust form) with double precision arithmetic. The custom solver gave identical answers to 5-6 decimals and achieved a substantial reduction in total simulation run time.

An alternate approach to the solution of (4.15) is to use a series approximation to the inverse of \([M]\). This approach is valid if the time-varying part of the mass matrix is small. Thus if,

\[ [M] = [M]_I[I + \Delta M] \]  

(4.17)

then,

\[ [M]^{-1} = [I + \Delta M]^{-1}[M]_I^{-1} = [I - \Delta M][M]_I^{-1} \]  

(4.18)
if $|\Delta M|$ is small. The inversion of $[M_I]$ could be done once in the initialization portion of the simulation.

4.4 Body Orientation Parameters

Three equivalent sets of parameters to describe the orientation of the body reference frame with respect to the Earth frame are maintained in the simulation. The three sets are the Euler angles ($\psi$, $\theta$, $\phi$), the quaternions ($e_0$, $e_1$, $e_2$, $e_3$), and the elements of the direction cosine matrix ($l_{xx}$, $l_{xy}$, ..., $l_{zz}$). These parameters are calculated by two separate methods according to the logical switch, LEULER. If LEULER is selected, then the three sets of orientation parameters are determined by integrating the time derivatives of the Euler angles, $\dot{\psi}$, $\dot{\theta}$, $\dot{\phi}$. If LEULER is not selected, then all the orientation parameters are determined from integrating the time derivatives of the quaternions (Euler parameters). The quaternion method was implemented first and avoids the problem of a singularity that occurs in the Euler angle derivatives when the pitch angle, $\theta$, is $90^\circ$. The singularity is associated with $\theta$ because of the order of application of the Euler angle rotations in transforming from the Earth frame to the body frame, that order being heading ($\psi$), pitch ($\theta$), and roll ($\phi$). If the $\theta = 90^\circ$ region is avoided, the two methods should produce the same answer to 3-4 decimals. The Euler angle integrations were added later so the Euler angles would occur as states in the simulation and therefore linear analysis using the Euler angles as state variables could be easily performed. Time derivatives are calculated and integrated for both the Euler angles and the quaternions at all times in the simulation. The effect of LEULER is to select one set of integrated outputs and ignore the other. Equations 4.19 through 4.31 below can be found among or derived from the equations in Appendix E of Gainer and Hoffman (1972).

4.4.1 Euler Angles

The time derivatives of the Euler angles are given by:

\[
\begin{align*}
\dot{\phi} &= p + \{\cos(\theta)\}^{-1}(\sin(\phi)\sin(\theta)q + \cos(\phi)\sin(\theta)r) \\
\dot{\theta} &= \cos(\phi)q - \sin(\phi)r \\
\dot{\psi} &= \{\cos(\theta)\}^{-1}(\sin(\phi)q + \cos(\phi)r)
\end{align*}
\]

(4.19)

In the simulation implementation of (4.19), the following expression is used for $\cos(\theta)$ where division by $\cos(\theta)$ is called for,

\[
C_\theta = \begin{cases} \varepsilon \frac{\theta}{|\theta|} & \text{if } |\cos(\theta)|l < \varepsilon = 10^{-10} \\ \cos(\theta) & \text{otherwise} \end{cases}
\]

(4.20)

so that division by zero when the pitch angle is at $90^\circ$ is avoided. States created by integrating the derivatives are subscripted with "x" to denote the fact that they may be ignored later depending on the choice of LEULER.
\[
\psi_x = \int_0^t \dot{\omega} dt + \psi_{ic} \\
\theta_x = \int_0^t \dot{\theta} dt + \theta_{ic} \\
\phi_x = \int_0^t \dot{\phi} dt + \phi_{ic} \tag{4.21}
\]

### 4.4.2 Quaternions

The derivatives of the quaternions are given by:

\[
\begin{bmatrix}
\dot{e}_0 \\
\dot{e}_1 \\
\dot{e}_2 \\
\dot{e}_3
\end{bmatrix} = \begin{bmatrix}
e_0 & -e_1 & -e_2 & -e_3 \\
e_1 & e_0 & -e_3 & e_2 \\
e_2 & e_3 & e_0 & -e_1 \\
e_3 & -e_2 & e_1 & e_0
\end{bmatrix} \begin{bmatrix}
p \\
q \\
r
\end{bmatrix} \tag{4.22}
\]

Define

\[
e = e_0 + ie_1 + je_2 + ke_3 = \{e_0 \ e_1 \ e_2 \ e_3\} \quad \text{and} \quad w = ip + jq + kr = \{0 \ p \ q \ r\}
\]

where the following rules of multiplication govern the i, j, k basis vectors.

\[
ij = -ji = k, jk = -kj = i, ki = -ik = j, \text{ and } ii = jj = kk = -1.
\]

Note that the complex conjugate of \(e\), the quaternion vector, is given by \(\bar{e} = e_0 - ie_1 - je_2 - ke_3\).

Observing that the product \(ew\) is given by,

\[
ev = -pe_1 - qe_2 - re_3 \\
+ i[ppe_0 - qe_3 + re_2] \\
+ j[ppe_3 + qe_0 - re_1] \\
+ k[-pe_2 + qe_1 + re_0] \tag{4.23}
\]

Equation (4.22) can be rewritten as,

\[
\dot{e} = ew \quad \text{or} \quad \bar{e} = \bar{we} \quad \text{where} \quad e = \begin{bmatrix}
e_0 \\
e_1 \\
e_2 \\
e_3
\end{bmatrix}, \quad \bar{e} = \begin{bmatrix}
e_0 \\
-e_1 \\
-e_2 \\
-e_3
\end{bmatrix} \tag{4.24}
\]

26
where left multiplication by \( e \) is equivalent to left multiplication by the \( 4 \times 4 \) matrix of equation 4.22. The components of the quaternion rate, \( \dot{e} \), are then integrated to produce quaternion states.

\[
\dot{e}_{j0x} = \int_0^t \dot{e}_j \, dt + e_{jic} \quad (j = 0, 3) \tag{4.25}
\]

The quaternions are used as the generating set from which the other two equivalent set of orientation parameters are derived. The quaternions in their unnormalized form are calculated according to the value of \( \text{LEULER} \). The additional zero subscript on the quaternions serves to indicate their unnormalized status.

\[
e_{00} = \begin{cases} 
\cos(\psi_2)\cos(\theta_2)\cos(\phi_2) + \sin(\psi_2)\sin(\theta_2)\sin(\phi_2) & \text{LEULER=}.T. \\
\cos(\psi_2)\cos(\theta_2)\cos(\phi_2) + \sin(\psi_2)\sin(\theta_2)\sin(\phi_2) & \text{LEULER=}.F. 
\end{cases} \tag{4.26.a}
\]

\[
e_{10} = \begin{cases} 
\cos(\psi_2)\cos(\theta_2)\sin(\phi_2) + \sin(\psi_2)\sin(\theta_2)\cos(\phi_2) & \text{LEULER=}.T. \\
\cos(\psi_2)\cos(\theta_2)\sin(\phi_2) + \sin(\psi_2)\sin(\theta_2)\cos(\phi_2) & \text{LEULER=}.F. 
\end{cases} \tag{4.26.b}
\]

\[
e_{20} = \begin{cases} 
\cos(\psi_2)\sin(\theta_2)\cos(\phi_2) + \sin(\psi_2)\cos(\theta_2)\sin(\phi_2) & \text{LEULER=}.T. \\
\cos(\psi_2)\sin(\theta_2)\cos(\phi_2) + \sin(\psi_2)\cos(\theta_2)\sin(\phi_2) & \text{LEULER=}.F. 
\end{cases} \tag{4.26.c}
\]

\[
e_{30} = \begin{cases} 
\sin(\psi_2)\cos(\theta_2)\cos(\phi_2) + \cos(\psi_2)\sin(\theta_2)\sin(\phi_2) & \text{LEULER=}.T. \\
\sin(\psi_2)\cos(\theta_2)\cos(\phi_2) + \cos(\psi_2)\sin(\theta_2)\sin(\phi_2) & \text{LEULER=}.F. 
\end{cases} \tag{4.26.d}
\]

The quaternions are then normalized. Note that if \( \psi, \theta, \phi \) are small, then to first order, \( \psi = e_3, \theta = e_2, \phi = e_1, \) and \( e_0 = 1 \). The norm of the quaternion vector is formed,

\[
|e| = \left\{ e_{00}^2 + e_{10}^2 + e_{20}^2 + e_{30}^2 \right\}^{1/2} \tag{4.27}
\]

and then used to scale the quaternion components:

\[
e_j = e_{jo} / |e| \quad (j=0, 3) \tag{4.28}
\]
While not required for the following development, it is interesting to observe that:

\[
\begin{pmatrix}
1 + e_1^2 \\
0 \\
0 \\
0 \\
\end{pmatrix} = e e
\]  

(4.29)

### 4.4.3 Direction Cosine Matrix

The direction cosine matrix elements and the final Euler angle can then be derived from the normalized quaternions:

\[
\begin{pmatrix}
0 \\
l_{xx} \\
l_{yx} \\
l_{zx} \\
\end{pmatrix} = \bar{e} \begin{pmatrix} 0 \\ 1 \\ 0 \\ 0 \end{pmatrix} e
\]

(4.30)

\[
\begin{pmatrix}
0 \\
l_{xy} \\
l_{yy} \\
l_{zy} \\
\end{pmatrix} = \bar{e} \begin{pmatrix} 0 \\ 0 \\ 1 \\ 0 \end{pmatrix} e
\]

\[
\begin{pmatrix}
0 \\
l_{xz} \\
l_{yz} \\
l_{zz} \\
\end{pmatrix} = \bar{e} \begin{pmatrix} 0 \\ 0 \\ 0 \\ 1 \end{pmatrix} e
\]

where in expanded form, the first equation of (4.30) is given by,

\[
\begin{pmatrix}
0 \\
l_{xx} \\
l_{yx} \\
l_{zx} \\
\end{pmatrix} = \begin{bmatrix}
e_0 & e_1 & e_2 & e_3 \\
e_1 & e_0 & e_3 & -e_2 \\
e_2 & -e_3 & e_0 & e_1 \\
e_3 & e_2 & -e_1 & e_0 \\
\end{bmatrix} \begin{pmatrix} 0 \\ -e_1 \\ 0 \\ e_0 \end{pmatrix} = \begin{bmatrix}
e_0 & -e_1 & -e_2 & -e_3 \\
e_1 & e_0 & -e_3 & e_2 \\
e_2 & e_3 & e_0 & -e_1 \\
e_3 & -e_2 & e_1 & e_0 \end{bmatrix}
\]

(4.31)

Finally, the Euler angles can be calculated directly from the elements of the direction cosine matrix.

\[
\Psi = \tan^{-1}\left(\frac{l_{xy}}{l_{xx}}\right)
\]

\[
\Theta = \sin^{-1}\left(l_{xz}\right)
\]

\[
\Phi = \tan^{-1}\left(\frac{l_{yz}}{l_{zz}}\right)
\]

(4.32)
5. AERODYNAMIC MODEL

5.1 Aerodynamic Data Sources

The aerodynamic characteristics of the F/A-18 are discussed in detail in MDC A7247, vol. 1, 2. The low α report, (MDC A7247, vol. 1), describes the force and moment build-up for three basic configurations (maneuvering, catapult and approach) in the angle-of-attack range of -10° to +40°. The maneuvering configuration is described in section 3 of MDC A7247, vol 1, while the low speed/high lift configurations (approach and catapult) are described in section 4 of MDC A7247, vol. 1. MDC A7247, vol. 2 describes the force and moment build-up for the maneuvering configuration in the angle-of-attack range of +40° to +90°. In the MDC batch simulation code (discussed in section 1.2 of this report) four separate force and moment build-ups; "clean", "power approach", "take-off", and "high" are implemented. The first three configurations of the MDC batch simulation code, ("clean", "power approach", and "take-off"), correspond to the three configurations of MDC A7247, vol. 1, ("maneuvering", "approach", and "catapult"). The fourth build-up in the MDC batch simulation code corresponds to the high-angle-of-attack, maneuvering configuration of MDC A7247, vol. 2. The "maneuvering" configuration equations of MDC A7247, vol. 1 and the "clean" configuration equations of the MDC batch simulation code are slightly different. The MDC A7247, vol. 1 "maneuvering" build-up has increments due to stores while the MDC batch simulation code "clean" build-up has increments due to gear deployment.

The simulation aerodynamic model described in this report is a combination of the maneuvering configurations described in MDC A7247, vol. 1, 2 and in the MDC batch simulation code with a few small extensions extracted from the high-lift configurations. In addition, MDC report A8575 contains background material, including a history of configuration development, a history of the substantiating wind-tunnel testing, and propulsion system characteristics.

As required by the simulation equations of motion discussed in section 4 of this report, the total aerodynamic force and moment coefficients are calculated in two parts. The portion of the total coefficient that is an explicit function of airplane velocities or control surface positions, the steady flow part, is calculated in subroutine SFAERRF. The part of the total coefficient that is proportional to airplane acceleration, the unsteady part, is calculated in subroutine USAERRF. The steady flow result is the sum of the static components plus the effect of body angular rates. The unsteady part includes the effect of the time rate of change of angle of attack or sideslip.

The moment coefficients and input velocities are defined about the aerodynamic reference center, (a.r.c.), which is defined in Table 5.1.

<table>
<thead>
<tr>
<th>Table 5.1. Aerodynamic Reference Center Coordinates</th>
</tr>
</thead>
<tbody>
<tr>
<td>Fuselage Station (FS), in.</td>
</tr>
<tr>
<td>Buttock Line (BL), in.</td>
</tr>
<tr>
<td>Water Line (WL), in.</td>
</tr>
</tbody>
</table>

The (FS/BL/WL) coordinates define a body-fixed axes system. The body axes system used in the equations of motion is centered at the center of gravity, aligned with the (FS/BL/WL) system, but has the sign convention of +x forward, +y out the right wing, and +z down (figure 3-1).

There are two logical variables that affect the coefficient calculations in the simulation described in this report, LQSE and LRTE. If the quasi-static-elastic logical, (LQSE), is true, then all the flex/rigid increments and effectiveness factors that were in the original model remain in effect. If LQSE is
false, then all the flex/rigid coefficients are set to the values they approach as air density, and therefore deformation, goes to zero. Setting LQSE false causes the aerodynamic forces and moments appropriate to the wind-tunnel-shape, which is not necessarily the jig-shape, of the airplane to be calculated. The LQSE option allows the use of the same code in a simulation where the flexible modes are actively modeled. The second logical is the real-time-equivalent flag (LRTE). If LRTE is true, then various differences that exist between the aerodynamic model used in the LaRC real-time simulation (dmsfl8) and the ACSL simulation described in this report are removed. These differences are discussed in section 5.5.2 "(Leading-Edge Flap Effects (Y,l,n))", section 5.5.5 ("Rudder Effects"), and section 5.5.9 ("Effect of Airplane Asymmetries (Y,l,n)") of this report.

The difference between the two aerodynamic models arises from changes made to the f18bas simulation math model that were not duplicated in the LaRC real-time simulation. The first of these changes was the inclusion of a rolling moment increment, \( \Delta C_{lasm} \), that is a function only of angle of attack, \( \alpha \), and nonzero for \( \alpha > 40^\circ \). The effect is to introduce a rolling disturbance as the simulated airplane moves through the 40° to 60° angle-of-attack region. The term arises from nose asymmetries and is discussed on pages 4-20, 21 of MDC A7247, vol. 2 and section 5.5.9 ("Effect of Airplane Asymmetries (Y,l,n)") of this report. The dmsfl8 simulation has the term \( \Delta C_{lasm} \) zeroed out. The second change is the inclusion of a nonzero estimate for \( C_{L\delta_n} \) (lift coefficient per unit leading-edge flap) for the case of \( 40^\circ < \alpha < 45^\circ \) and leading-edge flap position different from the scheduled value. This change is discussed in section 5.3.4 ("Leading-Edge Flap Effects") of this report. The third difference is the inclusion of rudder toe-in effects on drag, pitch, and lift in the ACSL simulation. Rudder toe-in can induce significant pitch moment and is an appropriate effect to include in a simulation supporting agility research. Symmetric rudder effects on pitch are discussed in section 5.3.9 ("Rudder Effects") of this report.

In the reconstruction equations, the total aerodynamic force and moment coefficients are built up from a large collection of intermediate coefficients. An attempt has been made to adopt symbolic conventions that indicate the source and purpose of the intermediate coefficients. Typically, the total force or moment coefficient consists of a "basic quantity" plus additional coefficients. The "basic contribution" is denoted by a zero subscript and is a function of Mach and either angle of attack or sideslip. For the "basic contribution", the controls are at a nominal position (typically zero) and the airplane is undeformed. Additional coefficients that represent increments to another coefficient (basic or otherwise) will begin with 'A'. Increments due to 'x' are the result of evaluating a tabular function where 'x' was an input. Coefficients that resemble classic stability derivatives and are to be multiplied by the appropriate control or nondimensional quantity will have no 'A' symbol.

### 5.2 Control Surface Sign Conventions

The control surface sign convention used in the aerodynamic model follows the convention established in MDC A7247, vol. 1. The terms "stabilator" and "horizontal tail" are used interchangeably in various MDC documents. MDC stability and control reports that describe the aerodynamic model (MDC A7247, vol. 1,2), tend to use the term "horizontal tail". MDC reports describing the flight control laws (MDC A4107, vol. 1 and MDC A7813, vol. 1,2,3), use "stabilator". "Stabilator" will be used in this document. In addition, the symbols \( \delta_H \) and \( \delta_{HT} \) are used interchangeably in MDC A7247, vol. 1 to refer to "horizontal tail" deflection.
Table 5.2. Control Deflection Sign Conventions

| \(\delta_{HR,L} = \text{right or left stabilator (horizontal tail), + trailing edge down}\) |
| \(\delta_{AR,L} = \text{right or left aileron, + trailing edge down}\) |
| \(\delta_{RR,L} = \text{right or left rudder, + trailing edge left}\) |
| \(\delta_{nR,L} = \text{right or left leading-edge flaps, + leading edge down}\) |
| \(\delta_{fR,L} = \text{right or left trailing-edge flaps, + trailing edge down}\) |
| \(\delta_H = \frac{1}{2} (\delta_{HR} + \delta_{HL}), \text{ symmetric (average) stabilator}\) |
| \(\delta_f = \frac{1}{2} (\delta_{fR} + \delta_{fL}), \text{ symmetric trailing-edge flap}\) |
| \(\delta_n = \frac{1}{2} (\delta_{nR} + \delta_{nL}), \text{ symmetric leading-edge flap}\) |
| \(\Delta\delta_H = \delta_{HL} - \delta_{HR}, \text{ differential stabilators (horizontal tails)}\) |
| \(\Delta\delta_f = \delta_{fL} - \delta_{fR}, \text{ differential trailing-edge flaps}\) |
| \(\Delta\delta_n = \delta_{nR} - \delta_{nL}, \text{ differential leading-edge flaps}\) |
| \(\delta_{RT} = \frac{1}{2} \{ \delta_{RR} - \delta_{RL} \}, \text{ symmetric rudder (both t.e.in)}\) |
| \(\delta_R = \frac{1}{2} \{ \delta_{RR} + \delta_{RL} \}, \text{ antisymmetric rudder (both t.e.left)}\) |
| \(\delta_{UA} = \frac{1}{4} \{ \delta_{fR} + \delta_{AR} + \delta_{fL} + \delta_{AL} \}, \text{ combined t.e. control}\) |

5.3 Lift and Pitch \((L,m)\)

The reconstruction equations that are used to compute the total lift and pitch coefficients are almost identical and are combined in a common form in equation (5.1). To the basic lift and pitch reconstruction equations (MDC A7247, vol. 1, section 3.1.1) the following have been added; (1) landing gear effects from the MDC batch simulation code (lines 805-906 of subroutine ARO18CN), and (2), rudder toe-in effects extracted from section 4.1.10 of MDC A7247, vol. 1. Replacing "\(X\)" in the equation below with "\(L\)" or "\(m\)" as appropriate will give the lift and pitch equations, respectively. The total lift/pitch coefficient is given by,

\[
C_X = C_{Xsf} + C_{X\alpha} \left( \frac{g^c}{2V} \right) \tag{5.1}
\]

where the steady flow lift/pitch coefficient is given by,
\begin{align}
C_{X_{sf}} &= C_{X_0} + \Delta C_{X_0} + \frac{1}{2} R^F_{C_X \delta_H} \left[ \Delta C_{X \delta_H L} + \Delta C_{X \delta_H R} \right] \\
&+ R^F_{C_L \delta_A} \left[ \Delta C_{X \delta_A L} + \Delta C_{X \delta_A R} \right] \\
&+ C_{X \delta_n} \delta_n + \Delta C_{X \delta_n} \delta_n + \left[ C_{X \delta_f} + \Delta C_{X \delta_f} \right] \delta_f \\
&+ \Delta C_{X \delta_{SB}} + \Delta C_{X \delta_{LG}} \delta_{LG} + \Delta C_{X \delta_{R}} + \Delta C_{X \delta_{RT}} \\
&+ \Delta C_{X \text{stores}} + \left[ C_{X_q} + \Delta C_{X_q} \right] \frac{q^e}{2V} 
\end{align} 

(5.2)

while the unsteady component of lift/pitch, i.e., proportional to nondimensional rate of change of angle of attack is given by,

\[ C_{X_{\alpha}} = C_{X_{\alpha_0}} + \Delta C_{X_{\alpha}} \] 

(5.3)

The individual components of the lift and pitch reconstruction equations, (5.2,5.3), are defined in sections (5.3.1) through (5.3.11). These components are for the most part calculated by performing linear interpolations according to tabulated functions. The variables used as input to the interpolation functions are normally limited to prevent extrapolation. Thus once the actual state or control variable reaches the limit of the data, no further change occurs in the coefficient. The input variables and the limits (if applied) are shown for each function look-up.

### 5.3.1 Basic Airframe Coefficient \((L,m)\)

The basic airframe lift/pitch coefficient for the rigid airplane with control surfaces undeflected is given by,

\[ C_{X_0} = \begin{cases} 
F_{C_{X_0}}(\alpha_{40.12}, M_{0.2}) & \alpha \leq 40^\circ; \delta_n = 0^\circ \\
F_{HC_{X_0}}(\alpha_{90.40}, M_{1.1}) & \alpha > 40^\circ; \delta_n = 34^\circ 
\end{cases} \] 

(5.4)

where the notation is defined as follows,

\[ F_{C_{X_0}}(\alpha_{1.2}, M_{0.2}) \triangleq \begin{cases} 
\text{the function } F_{C_{X_0}} \text{ as defined by data tables} \\
\text{is evaluated at an angle of attack and Mach number that are limited according to the brackets.} 
\end{cases} \]

At low angle of attack \((\alpha \leq 40^\circ)\), \(C_{X_0}\) refers to a zero stabilator, retracted flaps configuration. At high angle of attack \((\alpha > 40^\circ)\), basic lift/pitch, \(C_{X_0}\), refers to a configuration with zero stabilator.
and a leading-edge flap deflection of 34°. The elastic increment to the basic airframe lift/pitch coefficient is:

$$\Delta C_{x_0}^F = \begin{cases} \left( \frac{M_{0.2}}{4} \right) \int_0^{12} F_{DCxOF}(\alpha_{32}^{0.8}, M_{10.2}^{2}, \rho_{50000}^0) \text{ LQSE=.T.} \\ 0.0 \text{ LQSE=.F.} \end{cases} \quad (5.5)$$

In figures 3.1.1-1 through 3.1.1-22 of MDC A7247, vol. 1, the coefficients $C_{x_0}$ and $\Delta C_{x_0}^F$ are defined and combined for presentation into one coefficient.

### 5.3.2 Stabulator Effects ($L,m$)

Increments due to left and right stabulator (horizontal tail) deflections are,

$$\Delta C_{x_{HL,R}} = \begin{cases} F_{DCxDH}(\alpha_{140}^{40}, \delta_{HL,R}^{10.5}, M_{2}^{2}) \quad \alpha \leq 40 \\ F_{HDCxDH}(\alpha_{40}^{90}, \delta_{HL,R}^{10.5}, M_{2}^{1.1}) \quad \alpha > 40 \end{cases} \quad (5.6)$$

The elastic/rigid stabulator effectiveness factor is,

$$R_{C_{x_{H}}}^F = \begin{cases} F_{FRC}_{xDH}(M_{2}^{2}, \rho_{50000}^0) \text{ LQSE=.T.} \\ 1.0 \text{ LQSE=.F.} \end{cases} \quad (5.7)$$

### 5.3.3 Aileron Effects ($L,m$)

The lift/pitch increments due to left and right aileron deflections are,

$$\Delta C_{x_{AL,R}} = \begin{cases} F_{DCxDA}(\alpha_{140}^{40}, \delta_{AL,R}^{25}, M_{2}^{2}) \quad \alpha \leq 40 \degree \\ F_{HDCxDA}(\alpha_{40}^{90}, \delta_{AL,R}^{25}, M_{2}^{1.2}) \quad \alpha > 40 \degree \end{cases} \quad (5.8)$$

The elastic/rigid aileron effectiveness factor has been replaced by a flight-test derived quantity, a "flight/rigid" factor. This factor is larger than unity in the "rigid" limit because it reflects the configuration change that occurred between 1979 and 1984 in which the aileron span was increased outboard to the wingtip, (MDC A8575, page 1-4). The data in $F_{DCxDA}$ and $F_{HDCxDA}$ are for the small aileron (MDC A7247, vol. 1, page 3-357). Note that $R_{CL-\delta_A}^{CL}$ is used in both the lift ($C_{L_{sf}}$) and pitch ($C_{m_{sf}}$) equations.

$$R_{C_{L-\delta_A}}^{CL} = \begin{cases} F_{FFCLDA}(M_{2}^{2}, \rho_{50000}^0) \text{ LQSE=.T.} \\ 1.25 \text{ LQSE=.F.} \end{cases} \quad (5.9)$$
5.3.4 Leading-Edge Flap Effects (L,m)

The assumption in MDC A7247, vol. 1,2 and the MDC batch simulation code is that the leading-edge flaps are commanded according to the maneuvering flap schedule and will remain fixed at 34° if angle of attack is above 40°. If angle of attack is above 40°, $C_{X_0}$, defined in equation (5.4), includes the effect of the nonzero leading-edge flaps. Accordingly, $C_{X_{\delta n}}$, the lift/pitch per degree of leading-edge flap, is not defined in MDC A7247, vol. 2 and is set to zero in the MDC batch simulation code if $\alpha > 40°$. As a result, when the simulated airplane transitions from the low angle-of-attack database ($\alpha \leq 40°$) to the high angle-of-attack database ($\alpha > 40°$), a potential discontinuity can arise. If the leading-edge flaps are at 34° when the simulation goes through $\alpha=40°$, no discontinuity in $C_{X_0}$ occurs. However, if the leading-edge flaps are not on schedule, then a discontinuity in $C_{X_0}$ exists. To remove this potential discontinuity in the $fl8bas$ simulation, $C_{X_{\delta n}}$ is not set to zero abruptly at $\alpha=40°$, but rather is ramped to zero as angle of attack goes from 40° to 45°. Furthermore, when angle-of-attack is above 40°, $C_{X_{\delta n}}$ is multiplied by the difference between leading-edge flaps and 34°, the position at which the high angle-of-attack $C_{X_0}$ data was taken, instead of the total $\delta_n$. Thus,

$$C_{X_{\delta n}} = \begin{cases} 
F_{CXM_{\delta n}} (\alpha=40°, M|_{\delta_n}) & \alpha \leq 40 \\
\left(\frac{45 - \alpha}{5}\right) F_{CXM_{\delta n}} (\alpha=40°, M|_{\delta_n}) & \alpha > 40; \text{ LRTEN= .F.} \\
0.0 & \alpha > 40; \text{ LRTEN= .T.}
\end{cases} \quad (5.10)
$$

where

$$\delta_n = \begin{cases} 
\delta_n & \alpha \leq 40 \\
\delta_n - 34 & \alpha > 40
\end{cases} \quad (5.11)
$$

The elastic increments to the leading-edge flap sensitivity for lift and pitch are,

$$\Delta C_{L_{\delta n}}^F = \begin{cases} 
\left(\frac{M - 0.6}{0.2}\right) F_{DCDLNF} (\alpha|_{\delta_n}^{32}, M|_{\delta_n}^{1.1}, H_{\rho}^{60000}) & \text{LQSEN= .T.} \\
0.0 & \text{LQSEN= .F.}
\end{cases} \quad (5.12)
$$

and

$$\Delta C_{m_{\delta n}}^F = \begin{cases} 
\left(\frac{M - 0.2}{0.4}\right) F_{DCMDNF} (\alpha|_{\delta_n}^{32}, M|_{\delta_n}^{1.1}, H_{\rho}^{60000}) & \text{LQSEN= .T.} \\
0.0 & \text{LQSEN= .F.}
\end{cases} \quad (5.13)$$
The factor \( \left( \frac{M - 0.6}{0.2} \right)_0 \) serves to ramp in the full value of \( \Delta C_{L \delta n}^F \) as Mach goes from 0.6 to 0.8.

Similarly, \( \left( \frac{M - 0.2}{0.4} \right)_0 \) ramps in the full value of \( \Delta C_{m \delta n}^F \) by going from zero to one as Mach goes from 0.2 to 0.6.

5.3.5 Trailing-Edge Flap Effects (L,m)

The lift/pitch per degree deflection of symmetric trailing-edge flaps is,

\[
C_{X \delta f} = \begin{cases} 
F_{CXDF} (\alpha|^{40}, M|^{1.1}) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases}
\]  

(5.14)

The elastic increment to the trailing-edge flap sensitivity is,

\[
\Delta C_{X \delta f}^F = \begin{cases} 
\left( \frac{M - 0.2}{0.4} \right)_0 F_{DCXDF} (\alpha|^{32}, M|^{1.6}, H|^{60000}) & \alpha \leq 40^\circ; \text{LQSE=7.7} \\
0.0 & \text{otherwise}
\end{cases}
\]  

(5.15)

5.3.6 Speed Brake Effects (L,m)

The increments due to speed brake deflection are slightly different for lift and pitch. The lift increment is to be multiplied by normalized speed brake deflection, \( \frac{\delta_{SB}}{60} \). For the low angle-of-attack case, the pitch increment is itself a function of speed brake and no multiplier is needed.

\[
\Delta C_{L \delta SB} = \begin{cases} 
\left( \frac{\delta_{SB}}{60} \right) F_{DCLS} (\alpha|^{40}, M|^{1.2}) & \alpha \leq 40^\circ \\
\left( \frac{\delta_{SB}}{60} \right) F_{HDCLS} (\alpha|^{90}, M|^{1.2}) & \alpha > 40^\circ 
\end{cases}
\]  

(5.16)

\[
\Delta C_{m \delta SB} = \begin{cases} 
F_{DCMSB} (\alpha|^{40}, M|^{1.6}, \delta_{SB}|^{60}) & \alpha \leq 40^\circ \\
\left( \frac{\delta_{SB}}{60} \right) F_{HDCMSB} (\alpha|^{90}, M|^{1.2}) & \alpha > 40^\circ 
\end{cases}
\]  

(5.17)
5.3.7 Stores \((L, m)\)

The increment due to stores is discussed in MDC A7247, vol. 1, section 3.1.8, for the cases of Escort, Escort Overload, and Interdiction mission loadings. The quantity is currently set to zero in the \(fl8bas\) simulation described in this report.

\[
\Delta C_{x_{\text{stores}}} = 0.0
\]  

(5.18)

5.3.8 Landing Gear Effects \((L, m)\)

Increments to lift, pitch, and drag due to landing gear deployment are discussed on pages 4-75 and 4-76 of reference MDC A7247, vol. 1. In MDC A7247, vol. 1, landing gear increments are included only for the high-lift (take-off and approach) configurations. In the MDC batch simulation, landing gear increments are included in the lift, pitch, and drag build-up for the maneuvering ("clean") configuration. The increments used in the MDC batch simulation for the maneuvering configuration are different than those shown on 4-76 of MDC A7247, vol. 1. The increments used in the \(fl8bas\) simulation described in this report are those of MDC batch simulation. These increments are to be multiplied by normalized landing gear deployment. While studies to date have had no requirement for the aerodynamic effects of the landing gear being included, there is virtually no extra computational cost as the code calculating the coefficients is bypassed if the gear is retracted.

\[
\Delta C_{x_{\text{LG}}} = \begin{cases} 
F_{CXLG} (\alpha \parallel_{2}^{30}) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases}
\]  

(5.19)

5.3.9 Rudder Effects \((L, m)\)

The increment to lift due to antisymmetric rudder is included in the high lift configurations described in section 4.1.10 of MDC A7247, vol. 1, but not in the maneuvering configuration. The lift increment is set to zero in the \(fl8bas\) simulation described in this report. A nonzero pitch increment is included in the \(fl8bas\) simulation,

\[
\Delta C_{l\delta_{R}} = 0.0
\]  

(5.20)

\[
\Delta C_{m\delta_{R}} = \begin{cases} 
F_{DCMDR} (\alpha \parallel_{40}^{40}, |\delta_{R}| \parallel_{0}^{30}, M \parallel_{2}^{2}) & \alpha \leq 40^\circ \\
F_{HDCMDR} (\alpha \parallel_{40}^{90}, |\delta_{R}| \parallel_{0}^{30}, M \parallel_{2}^{1.2}) & \alpha > 40^\circ 
\end{cases}
\]  

(5.21)

Symmetric rudder is used in approach and landing, but is not part of the nominal maneuvering configuration model. While the pitch channel of the flight control system makes no use of symmetric rudder in the auto-flap-up (AFU), maneuvering mode, future agility-oriented research control laws may employ such a command. Therefore, increments in lift/pitch due to symmetric rudder (toe-in) have been added to the maneuvering configuration by using the increment developed for the high-lift configurations and discussed in section 4.1.10 of MDC A7247, vol. 1. The increments due to symmetric rudder for the \(fl8bas\) simulation are,
\[
\Delta C_{X_{\delta_{RT}}} = \begin{cases} 
  F_{DCXDT} (\alpha|^{40}_{-10}, \delta_{RT}|^{30}_{-15}, \delta_f/A|^{45}_0) & \alpha \leq 40^\circ \\
  0.0 & \alpha > 40^\circ
\end{cases}
\] (5.22)

Since the rudder toe-in coefficient was developed for the low speed/high lift configurations, there is no associated flex/rigid increment or effectiveness factor (page 4-5 of MDC A7247, vol. 1).

5.3.10 Pitch Rate (L,m)

The pitch rate derivative for lift/pitch is,
\[
C_{X_q} = \begin{cases} 
  F_{CXQ} (\alpha|^{40}_{-4}, M|^{2.2}_2) & \alpha \leq 40^\circ \\
  F_{HCXQ} (\alpha|^{90}_{40}, M|^{1.1}_2) & \alpha > 40^\circ
\end{cases}
\] (5.23)

The elastic increment to the pitch derivative for lift/pitch is,
\[
\Delta C_{X_q}^F = \begin{cases} 
  F_{DCXQF} (M|^{2.2}_2, H_p|^{60000}_0) & \text{LQSE=.T.} \\
  0.0 & \text{LQSE=.F.}
\end{cases}
\] (5.24)

5.3.11 Angle-of-Attack Rate (L,m)

The angle-of-attack rate derivative for lift/pitch for the rigid airplane is,
\[
C_{X_{\dot{\alpha}}} = \begin{cases} 
  F_{CXAD} (\alpha|^{40}_{-4}, M|^{2.2}_2) & \alpha \leq 40^\circ \\
  F_{HCXAD} (\alpha|^{90}_{40}, M|^{1.1}_2) & \alpha > 40^\circ
\end{cases}
\] (5.24)

while the elastic increment to the angle-of-attack rate derivative for lift/pitch is,
\[
\Delta C_{X_{\dot{\alpha}}}^F = \begin{cases} 
  \left(\frac{11-\alpha}{3}\right)^1 F_{DCXADF}(M|^{1.2}_2, H_p|^{60000}_0) & \text{LQSE=.T.} \\
  0.0 & \text{LQSE=.F.}
\end{cases}
\] (5.25)
5.4 Drag

Drag is not discussed in MDC A7247, vol. 1 for the maneuvering configuration. The total drag coefficient equation is taken from the MDC batch simulation and is repeated below,

\[ C_{D_{sf}} = C_{D_0} + \Delta C_{D_{CL}} + \frac{1}{2} \left[ \Delta C_{D\delta_{H_L}} + \Delta C_{D\delta_{H_R}} \right] + C_{D\delta_{H_1}} + C_{D\delta_{f}} \delta_{f} \]

\[ + \Delta C_{D\delta_{SB}} + \Delta C_{D\delta_{LG}} \delta_{LG} + \Delta C_{D\delta_{RT}} \]  \hspace{1cm} (5.26)

5.4.1 Basic Drag Coefficient

The basic drag coefficient is given by,

\[ C_{D_0} = \begin{cases} 
F_{CDO} \left( \alpha |^{40 \degree}, M |^{2.2} \right) & \alpha \leq 40 \degree \\
F_{HCDO} \left( \alpha |^{90 \degree}, M |^{1.1} \right) & \alpha > 40 \degree 
\end{cases} \]  \hspace{1cm} (5.27)

When in the low-angle-of-attack regime, an additional drag increment due to lift is calculated. However, \( C_{D_0} \) does not represent zero-lift drag. \( C_{D_0} \) has the characteristic parabolic shape of the standard drag polar and already includes the basic effects of lift on drag. An additional drag increment due to lift is defined in the MDC batch simulation as

\[ \Delta C_{D_{CL}} = \begin{cases} 
F_{DCDCL} \left( C_L |^{2.5}, M |^{1.8} \right) & \alpha \leq 40 \degree \\
0 & \alpha > 40 \degree 
\end{cases} \]  \hspace{1cm} (5.28)

\( \Delta C_{D_{CL}} \) represents small corrections to \( C_{D_0} \) and can be positive or negative. In the MDC batch simulation comments, \( \Delta C_{D_{CL}} \) is described as a correction "from tunnel drag to full-scale" and is presumably the result of flight data. Due to the explicit formulation of the equations of motion (section 4.3 of this document), \( C_L \) is not readily available in the f/8bas simulation. Therefore, in the f/8bas simulation implementation of (5.28), \( \Delta C_{D_{CL}} \) is a function of \( C_{L_{sf}} \) instead of \( C_L \). The difference in aircraft response induced by using \( C_{L_{sf}} \) instead of \( C_L \) in equation (5.28) is negligible.

5.4.2 Stabilator Drag Increment

The drag increments due to left and right stabilator (horizontal tail) deflection are given by:

\[ \Delta C_{D_{\delta_{H,L,R}}} = \begin{cases} 
F_{DCDHH} \left( \alpha |^{40 \degree}, \delta_{H,L,R} |^{10.5}, M |^{2.4} \right) & \alpha \leq 40 \degree \\
F_{HDCDHH} \left( \alpha |^{90 \degree}, \delta_{H,L,R} |^{10.5}, M |^{1.1} \right) & \alpha > 40 \degree 
\end{cases} \]  \hspace{1cm} (5.29)
5.4.3 Leading-Edge Flap Drag Derivative

The drag per degree of symmetric leading-edge flap is:

\[
C_{D\delta_n} = \begin{cases} 
F_{CDDN} (\frac{\alpha}{40}, M_{1.2}^{1.2}) & \alpha \leq 40^\circ \\
\left(\frac{45-\alpha}{5}\right)^{1/0} F_{CXDN} (\alpha=40, M_{1.2}^{1.2}) & \alpha > 40^\circ 
\end{cases}
\] (5.30)

5.4.4 Trailing-Edge Flap Drag Derivative

The drag per degree of symmetric trailing-edge flap is,

\[
C_{D\delta_f} = \begin{cases} 
F_{CDDF} (\frac{\alpha}{40}, M_{1.2}^{1.1}) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases}
\] (5.31)

5.4.5 Speed Brake Drag Derivative

The drag increment due to full speed brake deflection is,

\[
\Delta C_{DSB} = \begin{cases} 
\left(\frac{\delta_{SB}}{60}\right) F_{DCDSB} (\frac{\alpha}{40}, M_{1.2}^{1.2}) & \alpha \leq 40^\circ \\
\left(\frac{\delta_{SB}}{60}\right) F_{HDCDSB} (\frac{\alpha}{90}, M_{1.2}^{1.2}) & \alpha > 40^\circ 
\end{cases}
\] (5.32)

5.4.6 Landing Gear Drag Increment

The drag increment due to full landing gear deployment is,

\[
\Delta C_{DLG} = \begin{cases} 
F_{DCDLG} (\frac{\alpha}{30}) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases}
\] (5.33)

5.4.7 Rudder Drag Increment

As discussed in the lift/pitch term build-up, a drag increment due to symmetric rudder (toe-in) has been added to the maneuvering configuration by using the increment developed for the high-lift configurations and discussed in section 4.1.10 of MDC A7247, vol. 1. Recall that the low speed/high lift configurations are considered low-angle-of-attack configurations. As discussed in section 4.1.2.9, no elastic/rigid adjustments are defined for the rudder toe-in coefficients in MDC A7247, vol. 1.
\[ \Delta C_{D_{RT}} = \begin{cases} F_{CDDRT}(\alpha, \delta_{RT}, \delta_{f}/\delta_{A}) & \alpha \leq 40^\circ \\ 0.0 & \alpha > 40^\circ \end{cases} \] (5.33)

5.5 Side-Force, Roll, Yaw (Y,l,n)

As in the case of lift/pitch, the same reconstruction equation can be used for side force, roll and yaw. The appropriate equation is recovered by substituting "Y" (side force), "l" (roll), or "n" (yaw) for "X" in equation (5.34) below.

\[ C_{X_{sf}} = C_{X_0} + \Delta C_{X\beta} + \Delta C_{X\delta_{n}}\left(\frac{\delta_{n}}{25}\right) + \Delta C_{X\delta_{f}}\left(\frac{\delta_{f}}{20}\right) + C_{X\Delta X} \Delta \delta_{n} \]

\[ + C_{X\Delta \delta_{f}} + R_{CXR\delta_{n}} \left[ \Delta C_{X\delta_{AL}} + \Delta C_{X\delta_{AR}} \right] \]

\[ + \Delta C_{X\delta_{R}} R_{CXR\delta_{H}} R_{CX\delta_{R}} + R_{CXR\delta_{H}} C_{X\delta_{H}} \Delta \delta_{H} + \beta \Delta C_{X\delta_{SB}} \]

\[ + \Delta C_{X_{asm}} + C_{Xp} R_{CXp} \left(\frac{\beta^2}{2V}\right) + \left(C_{Xr} + \Delta C_{Xr}\right) \left(\frac{\beta^2}{2V}\right) \] (5.34)

5.5.1 Basic Airframe Coefficient (Y,l,n)

The basic airframe coefficient for the rigid airplane with controls at zero is given by,

\[ C_{X_0} = \begin{cases} k C_{X_{01}} + (1-k) C_{X_{02}} & \alpha \leq 40^\circ \\ F_{HCXO}(\beta, \alpha, \frac{\alpha}{40}, M_{1,2}) & \alpha > 40^\circ \end{cases} \] (5.35)

where,

\[ C_{X_{01}} = F_{CXO1}(\beta, \alpha, \frac{\alpha}{40}, M_{1,2}) \] (5.36.a)

\[ C_{X_{02}} = F_{CXO2}(\beta, \alpha, \frac{\alpha}{20}, M_{1,2}) \] (5.36.b)

and \( k = \frac{M_{1,1}}{1} \) (5.36.c)

5.5.2 Leading-Edge Flap Effects (Y,l,n)

If sideslip is nonzero, then symmetric leading-edge flap deployment produces a change in the lateral/directional coefficients. The increment due to full 25 degree deployment of symmetric leading-edge flaps in the presence of nonzero sideslip is given by,
\[
\Delta C_{Xn} = \begin{cases} 
\frac{\beta}{|\beta|} F_{DCXDN} \left( |\beta|^{20}, \alpha^{40}, M^{1.1} \right) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases}
\] (5.37)

where \(\Delta C_{Xn}\) is to be multiplied by a normalized leading-edge flap position in the appropriate reconstruction equation. The change in total coefficient per degree of differential leading-edge flap is given by:

\[
C_{Yn} = 0.0 \quad (5.38.a)
\]

\[
C_{I}n = \begin{cases} 
F_{C1FDN} \left( \bar{q}_1, M^{2.2} \right) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases} \quad (5.38.b)
\]

\[
C_{n}n = 0.0 \quad (5.38.c)
\]

where:

\[
\bar{q}_1 = \begin{cases} 
\bar{q} & \text{LQSE= T.} \\
0.0 & \text{LQSE= F.} 
\end{cases} \quad (5.39)
\]

### 5.5.3 Trailing-Edge Flap Effects \((Y,l,n)\)

Increments due to full 20 degree deployment of symmetric trailing-edge flaps in the presence of nonzero sideslip are,

\[
\Delta C_{Xf} = \begin{cases} 
\frac{\beta}{|\beta|} k f F_{DCXDF} \left( |\beta|^{20}, \alpha^{40}, M^{1.9} \right) & \alpha \leq 40^\circ \\
0.0 & \alpha > 40^\circ 
\end{cases} \quad (5.40)
\]

where as in the case of the leading-edge flaps, \(\Delta C_{Xf}\) is multiplied by normalized trailing-edge flap position in the appropriate reconstruction equation, and the factor \(k f\) is defined as,

\[
k_f = \frac{1.1-M}{2} \left| \frac{1}{0} \right. \quad (5.41)
\]

The change in total coefficient per degree of differential trailing-edge flap is given by,

\[
C_{Y}f = 0.0 \quad (5.42.a)
\]
\[ C_{\text{f} \Delta \delta_{f}} = \begin{cases} \text{FCIFDDF} (\alpha_{\text{H}_{\text{SL}}^{60000},|\delta_{\text{f}}^{25} |_{\text{M}^{2}}}) & \alpha \leq 40^\circ; \text{LQSE}=.T. \\ \text{FCIFDDF} (\alpha_{\text{H}_{\text{SL}}^{60000},|\delta_{\text{f}}^{25} |_{\text{M}^{2}}}) & \alpha \leq 40^\circ; \text{LQSE}=.F. \\ 0.0 & \alpha > 40^\circ \end{cases} \quad (5.42.b) \]

\[ C_{\text{n} \Delta \delta_{f}} = 0.0 \quad (5.42.c) \]

### 5.5.4 Aileron Effects (Y,l,n)

The increments due to left and right aileron deflection are given by,

\[ \Delta C_{X \delta_{\text{AL,R}}} = \begin{cases} k F_{\text{DCXDAL}} (\alpha_{|\delta_{\text{AL,R}}^{25} |_{\text{M}^{2}}}) & \alpha \leq 40^\circ \\ k F_{\text{HDCXDA}} (\alpha_{|\delta_{\text{AL,R}}^{25} |_{\text{M}^{2}}}) & \alpha > 40^\circ \end{cases} \quad (5.43) \]

where \( k = 1 \) for the left aileron and \( k = -1 \) for the right aileron.

The elastic/rigid ratio for aileron effectiveness is,

\[ R_{C_{\text{CY}} \delta_{A}} = \begin{cases} \text{FRCYDA} (\text{M}^{2}, \text{H}_{\text{SL}}^{60000}) & \text{LQSE}=.T. \\ \text{LQSE}=.F. \end{cases} \quad (5.44.a) \]

\[ R_{C_{\text{CL}} \delta_{A}} = \begin{cases} \text{FRCLDA} (\text{M}^{2}, \text{H}_{\text{SL}}^{60000}) & \text{LQSE}=.T. \\ \text{LQSE}=.F. \end{cases} \quad (5.44.b) \]

\[ R_{C_{\text{CN}} \delta_{A}} = \begin{cases} \text{FRCNDA} (\text{M}^{2}, \text{H}_{\text{SL}}^{60000}) & \text{LQSE}=.T. \\ \text{LQSE}=.F. \end{cases} \quad (5.44.c) \]

The elastic/rigid ratios assume values other than one in the rigid limit for the same reasons as discussed in section 5.3.3 of this report. The tabular look-up wind-tunnel data was taken before a configuration change that increased aileron area.

### 5.5.5 Rudder Effects (Y,l,n)

Increments due to antisymmetric (both t.e.left) rudder deflection are given by:

\[ \Delta C_{X \delta_{R}} = \begin{cases} \frac{\delta_{R}}{|\delta_{R}|} F_{\text{DCXDR}} (\alpha_{|\delta_{R}|}^{40}, |\delta_{R}|^{30}, \text{M}^{2}) & \alpha \leq 40^\circ \\ F_{\text{HDCXDR}} (\alpha_{\beta}^{90}, |\delta_{R}|^{10}, \delta_{R}) & \alpha > 40^\circ \end{cases} \quad (5.45) \]
The flex/rigid ratio for the effect of antisymmetric rudder is:

\[
R_{CX\delta_R}^F = \begin{cases} 
F_{FRCXDR} \left( M_2, H_p |^{60000}_0 \right) & \text{LQSE=.T.} \\
1.0 & \text{LQSE=.F.}
\end{cases}
\] (5.46)

An additional effectiveness factor that incorporates the effect of symmetric stabilator on the increment due to antisymmetric rudder at high angle of attack is given by,

\[
R_{CX\delta_H}^F = \begin{cases} 
F_{HRXDRH} \left( \alpha |^{90}_{40}, \delta_H |^{0}_{12} \right) & \alpha > 40^\circ; "X"="n"
\\
1.0 & \text{otherwise}
\end{cases}
\] (5.47)

5.5.6 Stabilator Effects (Y,l,n)

The derivative with respect to a differential stabilator, which is itself a function of angle of attack, symmetric stabilator, and Mach, is given by,

\[
C_{X\Delta\delta_H} = \begin{cases} 
F_{CXDDH} \left( \alpha |^{40}_{4}, \delta_H, M_2 \right) & \alpha \leq 40^\circ \\
F_{HCXDDH} \left( \alpha |^{90}_{40}, \delta_H, M_2 \right) & \alpha > 40^\circ
\end{cases}
\] (5.48)

The elastic/rigid ratio on the differential tail derivative is defined as,

\[
R_{CX\Delta\delta_H}^F = \begin{cases} 
F_{FRXDDH} \left( M_2, H_p |^{60000}_0 \right) & \text{LQSE=.T.; "X"="l"; LQSE=.T.}
\\
F_{FRXDDH} \left( M_2, H_p |^{60000}_0, \alpha |^{40}_0 \right) & \text{LQSE=.T.; "X"="n"; LQSE=.F.}
\\
1.0 & \text{LQSE=.F.}
\end{cases}
\] (5.49)

5.5.7 Dynamic Derivatives (Y,l,n)

The derivatives due to nondimensionalized roll rate are defined as,

\[
C_{XP} = \begin{cases} 
F_{CXP} \left( \alpha |^{40}_{4}, M_2, H_p |^{60000}_0 \right) & \alpha \leq 40^\circ; "X"="l"; \text{LQSE=.T.}
\\
F_{CXP} \left( \alpha |^{40}_{4}, M_2, H_p = 60000 \right) & \alpha \leq 40^\circ; "X"="l"; \text{LQSE=.F.}
\\
F_{CXP} \left( \alpha |^{40}_{4}, M_2 \right) & \alpha \leq 40^\circ; "X"="Y"or"n"
\\
F_{HCXP} \left( \alpha |^{90}_{40}, M_2 \right) & \alpha > 40^\circ
\end{cases}
\] (5.50)

while the effect of nondimensional yaw rate is given by,
\[
C_{Xr} = \begin{cases} 
F_{CXR} (\alpha |_{4}^{40}, M_{2}^{1.2}) & \alpha \leq 40^\circ \\
F_{HCXR} (\alpha |_{40}^{90}, M_{1.2}) & \alpha > 40^\circ 
\end{cases} 
\tag{5.51}
\]

The increment to yaw damping due to elastic deformation is given by,
\[
\Delta C_{Xr}^F = \begin{cases} 
F_{FDCXR} (M_{2}^{2}, H_{p}^{60000}) & \text{LQSE}=.T. \\
0.0 & \text{LQSE}=.F. 
\end{cases} 
\tag{5.52}
\]

A separate flex/rigid ratio on roll damping is calculated for side-force and yawing moment. The flexible effect on roll moment due to roll rate is included in the function used to calculate \( C_{\text{lp}} \).
\[
R_{CYp}^F = \begin{cases} 
F_{FRCYP} (M_{2}^{2}, H_{p}^{60000}) & \text{LQSE}=.T. \\
0.0 & \text{LQSE}=.F. 
\end{cases} 
\tag{5.53}
\]
\[
R_{Cnp}^F = \begin{cases} 
F_{FRCNP} (M=2, \alpha |_{0}^{40}) & \text{LQSE}=.T. \\
F_{FRCNP} (M=2, \alpha |_{0}^{40}) & \text{LQSE}=.F. 
\end{cases} 
\tag{5.54}
\]
\[
R_{C_{lp}}^F = 1.0 \quad \text{all conditions} \tag{5.55}
\]

5.5.8 Speed Brake Effects (\( Y,l,n \))

The speed brake increments shown below are due to full, normalized, speed brake deployment and are multiplied by sideslip angle in the reconstruction equations.
\[
\Delta C_{SB} = \begin{cases} 
\left(\delta_{SB}^{60}\right) F_{DCXSB} (\alpha |_{10}^{40} , |\beta| |_{0}^{20} , M_{2}^{2}) & \alpha \leq 40^\circ \\
\left(\frac{45-\alpha}{5}\right) \left(\delta_{SB}^{60}\right) F_{HDCXSB} (|\beta| |_{0}^{10} , M_{1.2}) & \alpha > 40^\circ 
\end{cases} 
\tag{5.56}
\]

5.5.9 Effect of Airplane Asymmetries (\( Y,l,n \))

A rolling moment is induced at zero sideslip and symmetric controls for angle of attack between 45° and 60°. This rolling moment is attributed (section 4.1.2 of [MDC A7247, vol. 2]) to asymmetries in the nose. The asymmetric increment is given by,
\[
\Delta C_{\text{asm}} = \begin{cases} 
0.0 & \alpha \leq 40^\circ \\
F_{\text{HC1ASM}} \left( \alpha \left[ \begin{array}{c} 90 \\ 40 \end{array} \right] \right) & \alpha > 40^\circ; "X" = "1"; \text{LRTE}=.F. \\
0.0 & \alpha > 40^\circ; "X" = "1"; \text{LRTE}=.T. \\
0.0 & \alpha > 40^\circ; "X" = "Y" \text{or} "n" 
\end{cases}
\]

(5.57)

5.6 Force and Moment Calculations

In this section we describe how the total aerodynamic forces and moments at the c.g. are calculated. The aerodynamic model has been worked up about an aerodynamic reference center. While it is common practice to transform the outputs of the aerodynamic model (force and moment coefficients) from the aerodynamic reference center to the c.g., it is less common to transform the inputs to the aerodynamic model. Both transformations are performed in the \textit{fl8bas} simulation in the interest of completeness. The practice of transforming the inputs has been seen by the authors in a simulation model for the X-29 and in section II of Gainer and Hoffman (1972).

First, the velocity of the air is subtracted from the inertial translational velocity of the airplane to get relative velocity (with respect to the air mass) at the c.g. The body frame components of velocity with respect to the air mass are given by,

\[
\begin{align*}
\begin{bmatrix} u_a \\ v_a \\ w_a \end{bmatrix} &= \begin{bmatrix} u \\ v \\ w \end{bmatrix} - \begin{bmatrix} u_{wg} \\ v_{wg} \\ w_{wg} \end{bmatrix} 
\end{align*}
\]

(5.58)

where \([u_{wg} v_{wg} w_{wg}]^T\) is the velocity of the air due to winds, turbulence, and gusts.

The velocity components relative to the air mass at the a.r.c. are given by,

\[
\begin{align*}
\begin{bmatrix} u_{arf} \\ v_{arf} \\ w_{arf} \end{bmatrix} &= \begin{bmatrix} u_a \\ v_a \\ w_a \end{bmatrix} + \begin{bmatrix} 0 & -r & q \\ r & 0 & -p \\ -q & p & 0 \end{bmatrix} \begin{bmatrix} x_{arf} \\ y_{arf} \\ z_{arf} \end{bmatrix} 
\end{align*}
\]

(5.59)

where \([x_{arf} y_{arf} z_{arf}]^T\) locates the a.r.c. in the c.g.-centered body frame. Rotational velocities at the c.g. can induce small changes in translational velocities at the a.r.c. Incidence angles (\(\alpha_{rf}\) and \(\beta_{rf}\)), airspeed, and Mach number, are then computed from relative velocities at the a.r.c.

\[
\begin{align*}
\alpha_{rf} &= \arctan\left( \frac{w_{arf}}{u_{arf}} \right) \\
\beta_{rf} &= \arcsin\left( \frac{v_{arf}}{V_{rf}} \right) \\
V_{rf} &= \sqrt{\frac{u_{arf}^2}{2} + \frac{v_{arf}^2}{2} + \frac{w_{arf}^2}{2}} \\
M_{rf} &= \frac{V_{rf}}{a}
\end{align*}
\]

(5.60)
Dynamic pressure ($\tilde{q}$) is left referenced to the c.g. The dynamic pressure in lbs/ft² is given by,

$$\tilde{q} = \frac{1}{2} \rho V_T^2$$  \hfill (5.61) 

where $\rho$ is the density in slugs/ft³. A density altitude, $H_p$, is calculated from the air density, $\rho$. $H_p$ is the altitude in feet that is appropriate for $\rho$ in the 1962 Standard Atmosphere tables. Air density can be varied as an independent variable if required (e.g., hot day conditions).

5.6.1 Steady Flow Outputs

The quantities defined in equations (5.60) and (5.61) are then combined with the body frame rotational rates ($p,q,r$), pressure altitude, the control surface deflections ($\{\delta\}$), and the reference dimensions ($\bar{c},b$), to serve as inputs to the aerodynamic model described in sections 5.2 through 5.5. Outputs of the aerodynamic model include the force and moment coefficients for steady flow conditions. The process is characterized by equation 5.62.

$$C_{\text{lift}} = f_{\text{aero}}(\alpha_{rf}, \beta_{rf}, V_{rf}, M_{rf}, \tilde{q}, H_p, \{\delta\}, \rho, q, r, \bar{c}, b)$$ \hfill (5.62) 

where "$l$" = "L", "D", "V", "T", "m", or "n". The lift and drag coefficients are converted to body axis components via,

$$
\begin{align*}
C_{x_{sf}} &= -\cos(\alpha_{rf})C_{D_{sf}} + \sin(\alpha_{rf})C_{L_{sf}} \\
C_{z_{sf}} &= -\sin(\alpha_{rf})C_{D_{sf}} - \cos(\alpha_{rf})C_{L_{sf}}
\end{align*}
$$  \hfill (5.63) 

The steady flow aerodynamic forces in the body frame are given by,

$$
[F]_A = \begin{Bmatrix} F_{X_{sf}} \\ F_{Y_{sf}} \\ F_{Z_{sf}} \end{Bmatrix}_A = \tilde{q}S \begin{Bmatrix} C_{x_{sf}} \\ C_{y_{sf}} \\ C_{z_{sf}} \end{Bmatrix}$$  \hfill (5.64) 

The steady flow aerodynamic moments in the body frame are given by,

$$
[M]_A = \begin{Bmatrix} M_{X_{sf}} \\ M_{Y_{sf}} \\ M_{Z_{sf}} \end{Bmatrix}_A = \tilde{q}S \begin{Bmatrix} b C_{L_{sf}} \\ b C_{m_{sf}} \\ -y_{arf} \end{Bmatrix} + \begin{bmatrix} 0 & -z_{arf} & y_{arf} \\ z_{arf} & 0 & -x_{arf} \\ -y_{arf} & x_{arf} & 0 \end{bmatrix} \begin{Bmatrix} F_{X_{sf}} \\ F_{Y_{sf}} \\ F_{Z_{sf}} \end{Bmatrix}_A$$  \hfill (5.65) 

As a simple sanity check, observe that a positive $x_{arf}$ implies the a.r.c. is ahead of the c.g., and a positive $F_{Z_{sf}}$ force applied at the a.r.c. induces a negative pitch moment, $M_Y$. 

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5.6.1 Unsteady Flow Outputs

We seek now to define the 6x6 apparent mass matrix defined in equation (4.13) (repeated below) that arises from the $C_{L\alpha}$ and $C_{m\alpha}$ stability derivatives.

\[
[M]_A = - \frac{\partial \{ F \}}{\partial \{ V \}}
\]  
(4-13)

First, in a process similar to equation (5.63), transform the $\alpha$ stability derivatives from stability to body frame components at the a.r.c.,

\[
\begin{align*}
C_{X\alpha} &= - \cos(\alpha_{rf})C_{D\alpha} + \sin(\alpha_{rf})C_{L\alpha} \\
C_{Z\alpha} &= - \sin(\alpha_{rf})C_{D\alpha} - \cos(\alpha_{rf})C_{L\alpha}
\end{align*}
\]  
(5.66)

In the fl8bas simulation, as is typically the case, $C_{D\alpha}$ is zero. Define some intermediate terms that have units of mass and mass-length.

\[
\begin{align*}
m_0 &= \bar{q} S \left( \frac{\bar{c}}{2V_{rf}} \right) \left( \frac{u_{arf}}{u_{arf}^2 + w_{arf}^2} \right), \text{slugs} \\
m_u &= m_0 C_{X\alpha}, \quad \text{slugs} \\
m_w &= m_0 C_{Z\alpha}, \quad \text{slugs} \\
m_q &= \bar{c} m_0 C_{m\alpha}, \quad \text{slug-ft}
\end{align*}
\]  
(5.67)

For notational convenience, let $V$ and $\omega$ denote the 3x1 column vectors associated with translational and rotational velocity, respectively,

\[
V = \{ u \ v \ w \}, \quad \omega = \{ p \ q \ r \}
\]  
(5.69)

The apparent mass matrix is given by,

\[
[M]_A = - \frac{\partial \{ F \}}{\partial \{ V \}} = \begin{bmatrix} [M_{VV}] & [M_{V\omega}] \\ [M_{\omega V}] & [M_{\omega\omega}] \end{bmatrix}
\]  
(5.70)

where,
\[
\frac{\hat{\omega}_{rf}}{u_{arf}} = \begin{pmatrix}
\frac{w_{arf}}{u_{arf}} \\
\end{pmatrix}
\]  

\[
[M_{VV}] = \begin{bmatrix}
m_u \hat{\omega}_{rf} & 0 & -m_u \\
0 & 0 & 0 \\
m_w \hat{\omega}_{rf} & 0 & -m_w
\end{bmatrix}, \text{slugs} \tag{5.71}
\]

\[
[M_{V\omega}] = \begin{bmatrix}
-m_u y_{arf} & m_u (x_{arf} + \hat{\omega}_{rf} z_{arf}) & -m_u \hat{\omega}_{rf} y_{arf} \\
0 & 0 & 0 \\
-m_w y_{arf} & m_w (x_{arf} + \hat{\omega}_{rf} z_{arf}) & -m_w \hat{\omega}_{rf} y_{arf}
\end{bmatrix}, \text{slug-ft} \tag{5.72}
\]

\[
[M_{\omega V}] = \begin{bmatrix}
-m_w y_{arf}^2 & m_w (x_{arf} + \hat{\omega}_{rf} z_{arf}) y_{arf} & -m_w \hat{\omega}_{rf} y_{arf}^2 \\
(-m_u z_{arf} + m_w x_{arf} + m_q) y_{arf} & (m_u z_{arf} + m_w x_{arf} + m_q) (x_{arf} + \hat{\omega}_{rf} z_{arf}) & (-m_u z_{arf} + m_w x_{arf} + m_q) \hat{\omega}_{rf} y_{arf} \\
m_u y_{arf}^2 & -m_u (x_{arf} + \hat{\omega}_{rf} z_{arf}) y_{arf} & m_u \hat{\omega}_{rf} y_{arf}^2
\end{bmatrix}, \text{slug-ft^2} \tag{5.73}
\]

and,

\[
[M_{\omega \omega}] = 
\begin{bmatrix}
-m_w y_{arf}^2 & m_w (x_{arf} + \hat{\omega}_{rf} z_{arf}) y_{arf} & -m_w \hat{\omega}_{rf} y_{arf}^2 \\
(-m_u z_{arf} + m_w x_{arf} + m_q) y_{arf} & (m_u z_{arf} + m_w x_{arf} + m_q) (x_{arf} + \hat{\omega}_{rf} z_{arf}) & (-m_u z_{arf} + m_w x_{arf} + m_q) \hat{\omega}_{rf} y_{arf} \\
m_u y_{arf}^2 & -m_u (x_{arf} + \hat{\omega}_{rf} z_{arf}) y_{arf} & m_u \hat{\omega}_{rf} y_{arf}^2
\end{bmatrix}, \text{slug-ft^2} \tag{5.74}
\]
5.7 Implementation of the aerodynamic model

As described in section 5.1, the aerodynamic force and moment coefficients are calculated in subroutines SFAERRF and USAERRF. In sections 5.7.1 and 5.7.2 the input/output variables of the subroutines SFAERRF and USAERF, respectively, are described.

5.7.1 SFAERRF - Input/Output List

The subroutine SFAERRF produces the total force and moment coefficients about the aerodynamic reference center for steady flow conditions (constant angle of attack and sideslip). The names of each input/output parameter as they appear in both the subroutine (SFAERRF) and in the fl8bas.csl code from which SFAERRF is called, are listed in tables 5.3 and 5.4. The density altitude is used as an input to the flex/rigid multipliers and increments. Ground clearance was used for ground effect calculations. The calculations associated with ground effect have been removed, but the parameter list was left unchanged in the interest of compatibility.

### Table 5.3. Input parameters for subroutine SFAERRF

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>SFAERRF</th>
<th>.csl</th>
</tr>
</thead>
<tbody>
<tr>
<td>a</td>
<td>angle of attack, degrees</td>
<td>ALPDEG</td>
<td>ALDGRF</td>
</tr>
<tr>
<td>β</td>
<td>sideslip angle, degrees</td>
<td>BETDEG</td>
<td>BEDGRF</td>
</tr>
<tr>
<td>M</td>
<td>Mach number</td>
<td>MACH</td>
<td>MACHRF</td>
</tr>
<tr>
<td>p</td>
<td>Body frame roll rate, rad/sec</td>
<td>P</td>
<td>P</td>
</tr>
<tr>
<td>q</td>
<td>Body frame pitch rate, rad/sec</td>
<td>Q</td>
<td>Q</td>
</tr>
<tr>
<td>r</td>
<td>Body frame yaw rate, rad/sec</td>
<td>R</td>
<td>R</td>
</tr>
<tr>
<td>H_p</td>
<td>Altitude above sea-level in a standard atmosphere equivalent to a given density, feet</td>
<td>ALT</td>
<td>HRF</td>
</tr>
<tr>
<td>H_gcl</td>
<td>Ground clearance, feet</td>
<td>HGCL</td>
<td>HGC</td>
</tr>
<tr>
<td>q</td>
<td>Dynamic pressure, lbs/ft²</td>
<td>QBAR</td>
<td>QBAR</td>
</tr>
<tr>
<td>c</td>
<td>Reference aerodynamic chord, feet</td>
<td>CREF</td>
<td>CWRF</td>
</tr>
<tr>
<td>b</td>
<td>Reference aerodynamic span, feet</td>
<td>BREF</td>
<td>BWRF</td>
</tr>
<tr>
<td>V</td>
<td>Total airspeed at the aero reference center, ft/sec</td>
<td>VTRF</td>
<td>VTRF</td>
</tr>
<tr>
<td>δ_H_R</td>
<td>Right stabilator (horizontal tail), positive trailing edge down (+ t.e.d), degrees</td>
<td>DHTR</td>
<td>DSR</td>
</tr>
<tr>
<td>δ_H_L</td>
<td>Left stabilator (horizontal tail), + t.e.d, degrees</td>
<td>DHTL</td>
<td>DSL</td>
</tr>
<tr>
<td>δ_A_R</td>
<td>Right aileron, + t.e.d, degrees</td>
<td>DAR</td>
<td>DAR</td>
</tr>
<tr>
<td>δ_A_L</td>
<td>Left aileron, + t.e.d, degrees</td>
<td>DAL</td>
<td>DAL</td>
</tr>
<tr>
<td>δ_R_R</td>
<td>Right rudder, + t.e. left, degrees</td>
<td>DRR</td>
<td>DRR</td>
</tr>
<tr>
<td>δ_R_L</td>
<td>Left rudder, + t.e. left, degrees</td>
<td>DRL</td>
<td>-DRL</td>
</tr>
<tr>
<td>δ_f_R</td>
<td>Right trailing-edge flap, + t.e.d, degrees</td>
<td>DTRF</td>
<td>DFR</td>
</tr>
<tr>
<td>δ_f_L</td>
<td>Left trailing-edge flap, + t.e.d, degrees</td>
<td>DTLF</td>
<td>DFL</td>
</tr>
<tr>
<td>δ_n_R</td>
<td>Right leading-edge flap, + l.e.d, degrees</td>
<td>DLRF</td>
<td>DNR</td>
</tr>
<tr>
<td>δ_n_L</td>
<td>Left leading-edge flap, + l.e.d, degrees</td>
<td>DLLF</td>
<td>DNL</td>
</tr>
</tbody>
</table>

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Table 5.3. Input parameters for subroutine SFAERRF (continued)

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>SFAERRF</th>
<th>.csl</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\delta_{SB}$</td>
<td>Speed brakes, 0 - 60, degrees</td>
<td>DSBK</td>
<td>DSB</td>
</tr>
<tr>
<td>$\delta_{LG}$</td>
<td>Normalized landing gear, 0 - 1, full down logical</td>
<td>DLG</td>
<td>DLG</td>
</tr>
<tr>
<td>logical</td>
<td>(.T.) Detailed print of intermediate variables on unit=20.</td>
<td>LDEBUG</td>
<td>LDEBUG</td>
</tr>
<tr>
<td>logical</td>
<td>(.F.) No action</td>
<td></td>
<td></td>
</tr>
<tr>
<td>logical</td>
<td>(.T.) Flex/rigid multipliers and increments calculated</td>
<td>LQSE</td>
<td>LQSE</td>
</tr>
<tr>
<td>logical</td>
<td>(.F.) Aero for rigid airplane, flex/rigid $\rightarrow$ 1.</td>
<td>LRTE</td>
<td>LRTE</td>
</tr>
<tr>
<td>logical</td>
<td>(.T.) Real time equivalent aero</td>
<td></td>
<td></td>
</tr>
<tr>
<td>logical</td>
<td>(.F.) Enhanced aerodynamic model</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Table 5.4. Output parameters for subroutine SFAERRF

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>SFAERRF</th>
<th>.csl</th>
</tr>
</thead>
<tbody>
<tr>
<td>$C_{Dsf}$</td>
<td>Total drag coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CDREFO</td>
<td>CDRFSF</td>
</tr>
<tr>
<td>$C_{Ysf}$</td>
<td>Total side-force coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CYREFO</td>
<td>CYRFSF</td>
</tr>
<tr>
<td>$C_{Lsf}$</td>
<td>Total lift coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CLREFO</td>
<td>CLRFSF</td>
</tr>
<tr>
<td>$C_{l_{sf}}$</td>
<td>Total roll coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CIREFO</td>
<td>CIRFSF</td>
</tr>
<tr>
<td>$C_{m_{sf}}$</td>
<td>Total pitch coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CMREFO</td>
<td>CMRFSF</td>
</tr>
<tr>
<td>$C_{n_{sf}}$</td>
<td>Total yaw coefficient at a.r.c. evaluated at $\alpha=0$</td>
<td>CNREFO</td>
<td>CNRFSF</td>
</tr>
</tbody>
</table>
### 5.7.2 USAERRF - Input/Output List

The subroutine USAERRF returns the lift and pitch derivatives with respect to the nondimensional rate-of-change of angle of attack. The names of each input/output parameter as they appear in both the subroutine (USAERRF) and in the fl8bas.csl code from which USAERRF is called, are listed in tables 5.5 and 5.6.

Table 5.5. Input parameters for subroutine USAERRF

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>SFAERRF</th>
<th>.csl</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\alpha$</td>
<td>angle of attack, degrees</td>
<td>ALPDEG</td>
<td>ALDGRF</td>
</tr>
<tr>
<td>M</td>
<td>Mach number</td>
<td>MACH</td>
<td>MACHRF</td>
</tr>
<tr>
<td>$H_p$</td>
<td>Altitude above sea-level in a standard atmosphere equivalent to a given density, feet</td>
<td>ALT</td>
<td>HRF</td>
</tr>
<tr>
<td>logical</td>
<td>(.T.) Detailed print of intermediate variables on unit=20.</td>
<td>LDEBUG</td>
<td>LDEBUG</td>
</tr>
<tr>
<td>logical</td>
<td>(.F.) No action</td>
<td>LQSE</td>
<td>LQSE</td>
</tr>
<tr>
<td>logical</td>
<td>(.T.) Flex/rigid multipliers and increments calculated</td>
<td>LQSE</td>
<td>LQSE</td>
</tr>
<tr>
<td>logical</td>
<td>(.F.) Aero for rigid airplane, flex/rigid -&gt; 1.</td>
<td>LQSE</td>
<td>LQSE</td>
</tr>
</tbody>
</table>

Table 5.6. Output parameters for subroutine USAERRF

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>SFAERRF</th>
<th>.csl</th>
</tr>
</thead>
<tbody>
<tr>
<td>$C_{L_\alpha}$</td>
<td>$\partial C_L / \partial \frac{\dot{\alpha}c}{2V}$</td>
<td>CLADRF</td>
<td>CLADRF</td>
</tr>
<tr>
<td>$C_{m_\alpha}$</td>
<td>$\partial C_m / \partial \frac{\dot{\alpha}c}{2V}$</td>
<td>CMADRF</td>
<td>CMADRF</td>
</tr>
</tbody>
</table>
6. ENGINE THRUST MODEL

The engine model takes inputs from the pilot throttle and an autothrottle command, uses current air data (altitude, Mach number, and dynamic pressure), and computes the engine forces acting on the airframe for the equations of motion described in section 4. This engine model is referred to as the "QT Half" model in MDC documentation and correspondence (MDC internal memorandum 338-5250, dated 5-Dec-80, from R.O. Michael and B.R. Williams), and apparently is a refined model (circa 1980) based on installed engine performance flight tests. It should be noted that the authors focused on implementing this model as provided, in order to facilitate comparison with an existing real-time simulation model. The authors are not able to explain some aspects of the architecture of this model -- these will be noted as appropriate in the text below.

The model from pilot/autopilot inputs to thrust determination for a given engine is represented graphically in figure 6.0. Since the airplane has two engines, this model is implemented in code by parallel sets of ACSL equations and external subroutine calls for the left and right engines. Although the autopilot input is provided for future use, in the current simulation this input, CAT, is set to zero. Therefore, PLA, the total throttle command, is equal to CP, the pilot throttle command.

![Figure 6.0. Engine Model Block Diagram](image)

6.1 Throttle Dynamics

PLA is input to the Throttle Dynamics, a straightforward servo model with throttle position, DPL, as its output. This servo model includes a limited integrator, which functions as a normal integrator as long as its output remains between the indicated limits {31, 130}. If the integrator output equals or exceeds these limits, the state derivative DPL_D is set to zero within the limited integrator macro and the integrator output is appropriately limited. The limited integrator block shown in figure 6.1 is the implementation provided by ACSL's built-in limited integrator command. This structure is shown for graphical convenience; in the ACSL simulation model, a
custom macro using IF condition tests is actually used. Either implementation should be equivalent; the custom macro was developed by the authors to retain control over the variable names of states and state derivatives [ACSL (1987)].

6.2 Static Performance

As shown in figure 6.2, throttle position (DPL), along with altitude (H), Mach number (MACH), and an internal engine dynamics state (VAE0) are input to the static performance module (Fortran subroutine ENG1). VAE0 is an artificial state created to break an algebraic loop for the static performance module. In the original specification, VAE is an input into the static performance module, and VAE is dependent on output THRC. VAE0 is created by passing VAE through a fast first order lag and is discussed further in section 6.5, Core Dynamics.

The outputs of the static performance module are engine thrust command (THRC), fuel flow (WF), idle thrust (TIDLE), maximum military power thrust (TMIL), minimum afterburner thrust (TAUGMN), maximum afterburner thrust (TAUGMX), and various gains and parameters for the engine dynamics (TESTV, GKI, TAU). THRC and WF are each computed as a table-lookup function, of H, MACH, and DPL. There are two table-lookup functions for THRC; one for military power throttle settings and one for afterburner throttle settings.
at a DPL (PLA after dynamics) of 106.5°, rather than the expected military/afterburner throttle position boundary of 88-91° (PLA).

TIDLE, TMIL, TAUGMN, and TAUGMX are computed for appropriate fixed throttle positions using the same table-lookup function as for THRC. TESTV, GK1, P1, P2, TAU are computed as table-lookup functions of TML.

THRC is used by two sets of engine dynamics running in parallel: Afterburner Dynamics and Core Dynamics. This will be described further below. GK1, TAU, TESTV, and TMIL are used in the Core Dynamics (see below). TAUGMN is used in the Discrete Event Logic (see below). WF, TIDLE, and TAUGMX are not currently used elsewhere in the ACSL simulation model.

6.3 Discrete Event Logic

As described above, the engine thrust command (THRC) is provided to two sets of engine dynamics running in parallel: Afterburner Dynamics and Core Dynamics. These dynamics provide a single thrust output that is used as the total net thrust for a given engine. The Discrete Event Logic (figure 6.3) is used to determine when to switch from one set of dynamics to the other, and implements code:

1) to select the appropriate thrust output from either Afterburner Dynamics or Core Dynamics;
2) to enable a smooth transition between the two dynamic systems by updating appropriate state variables -- this is accomplished in ACSL using DISCRETE blocks (one per engine) called by the ACSL SCHEDULE operator [ACSL (1987)].

The authors note that the Discrete Event Logic uses a thrust comparison test that is inconsistent with the switch test used in the static performance module to select the output of the thrust table lookup. The authors cannot explain why this is so; nor can we explain why this parallel dynamics architecture was chosen. It would seem more physically intuitive to implement an Afterburner Dynamics module that outputs an incremental thrust to be added to the Core Dynamics thrust to yield total net thrust.

![Figure 6.3. Discrete Event Logic](image)
6.4 Afterburner Dynamics

As shown in figure 6.4, THRC is one of three inputs to the Afterburner Dynamics. The physics of the MDC model are such that when the thrust command (THRC) exceeds the afterburner thrust (TAB), TAB integrates up at the rate ABUL. Conversely, when TAB is greater than THRC, TAB integrates down at the rate ABLL.

ABUL and ABLL are computed based on current values of altitude (H) and dynamic pressure (QBAR). The lower rate limit, ABLL, is computed as a function of H,

\[ ABLL = 0.0275H - 5500 \]  \hspace{1cm} (6.1)

The upper rate limit, ABUL, is computed in two steps. The first step is to compute an intermediate value as a function of QBAR,

\[ ABUL^{*} = 1.7QBAR^{2} - 12.8QBAR + 3000 \]  \hspace{1cm} (6.2)

ABUL is then computed by limiting ABUL* as,

\[ ABUL = \begin{cases} 
900 & \text{if } ABUL^{*} < 900 \\
ABUL^{*} & \text{if } 900 \leq ABUL^{*} \leq 4000 \\
4000 & \text{if } 4000 < ABUL^{*} 
\end{cases} \]  \hspace{1cm} (6.3)

In the ACSL implementation of this system, the error signal THRC minus TAB is multiplied by a large gain (200) to yield ZZAB. ZZAB is passed through a rate limiter and is appropriately limited to ABUL or ABLL to yield RTAB. RTAB is then integrated to yield TAB. Synchronization of the Afterburner Dynamics with the Core Dynamics is achieved by updating TAB with the last value of core engine thrust, TT, when transition from Core Dynamics to Afterburner Dynamics occurs. This has the effect of "restarting" the afterburner dynamics from the thrust value at transition.

![Figure 6.4. Afterburner Dynamics](image-url)
6.5 Core Dynamics

As shown in figure 6.5, THRC is one of two primary inputs to the Core Dynamics, which implements a second order dynamics approximation to a more complicated, higher order dynamic model of the turbomachinery used for batch analysis of the engine by its manufacturer. The other five inputs are variables that have been described previously: TESTV, GK1, P1, P2, TAU.

The error signal VAC is computed by subtracting VAF from THRC. VAC is multiplied by the gain GK1 and is passed through the rate limiter bounded by limits RTEUL and RTELL to yield VAE. The rate limits RTEUL and RTELL are the engine spool-up/down rate limits and are defined as CONSTANT variables in the ACSL simulation model. Therefore, although they have a "default" value, these limits can be altered at runtime [ACSL (1987)] by the user. The default values are ±5500.

![Diagram of Core Dynamics]

Figure 6.5. Core Dynamics

VAE is input to a low-pass filter to generate the artificial state VAE0 as described earlier to break the algebraic loop for the static performance module. The time constant for this filter is sufficiently small (50 rad/sec) to insure that all engine dynamics are unaffected by the filter. VAE is input to an integrator, yielding VAF. Synchronization of this integrator with the Afterburner Dynamics is achieved by updating VAF with the last value of afterburner engine thrust, TAB, when transition occurs from Afterburner Dynamics to Core Dynamics. This has the effect of "restarting" this integrator with the thrust value at transition.
VAF is the major component of the core engine thrust, represented by a rate-limited first order lag. VAF is used to form the error signal VAC as previously described. VAF is tested against TAUGMN in Discrete Event Logic to determine whether to initiate a transition between Core Dynamics and Afterburner Dynamics. VAF is supplied to the "Nonlinear Switch" [MDC internal memo 338-5250]. The "Nonlinear Switch" will be described below. VAF is summed with VAK to determine core engine thrust, TT.

The "Nonlinear Switch" can only be active when the core dynamics are being used. Inputs to this switch are VAF, VAC, TMIL and TESTV. At each simulation time step for which the condition

\[
\text{ABS} \left( \frac{\text{VAC}}{\text{TMIL}} \right) < \text{TESTV}
\]

is true, the "Nonlinear Switch" assigns VAH to the current value of VAF. Since the "Nonlinear Switch" is the only mechanism for defining VAH, it remains constant when the above condition is not true. TMIL is a function of Mach number and altitude; TESTV is a positive-valued function of VAE/TMIL, varying proportionally with the magnitude of VAE. Therefore VAH only changes when VAC is large relative to VAE (big change in throttle command).

Subroutine ENG2, coded in FORTRAN, is only called when the core dynamics are being used. The input is an internal engine dynamics parameter \(\frac{\text{VAF}}{\text{TMIL}}\). The output is a gain for the second order dynamics block (GK3).

VH1 is subtracted from VAH and the result is divided by TAU, yielding VH1D. VH1D is integrated to give VH1. Synchronization of this integrator with the Afterburner Dynamics is achieved by setting VH1 equal to VAH when transition occurs from Afterburner Dynamics to Core Dynamics. By "zeroing" the input signal to this integrator, this part of the dynamics is not active at transition.

VH1D is input to the 2nd Order Dynamics block, a transfer function with the following Laplace expression,

\[
\frac{\text{VAK}}{\text{VH1D}} = \frac{(P2)^2(\text{GK3})}{S^2 + 2(P1)(P2)S + (P2)^2(\text{GK3})}
\]

The VAK term provides the small "ballooning" effect for the engine described in MDC internal memo 338-5250 (1980). VAK is summed with VAF to give the total thrust for the Core Dynamics, TT.

6.6 Total Engine Thrust

The final total thrust for each engine, TH, is determined by the position of the AB/Core switch. If \(\text{THRF} \geq 0\), then TH is equal to the output of the Core Dynamics, TT; otherwise, TH is equal to the output of the Afterburner Dynamics, TAB.

6.7 Calculations for Equations of Motion

The equations of motion for the simulation, described in section 4, require the 3-axis body frame components of force and moment due to the thrust from the engines. Therefore, operations are performed on the final total thrust for each engine, TH, and then added together to yield these required force/moment components. Note that engine gyroscopic moment effects are not modeled.
In keeping with overall assumptions that an x-z plane of symmetry exists, the engines are assumed to be located symmetrically with respect to the body frame x-z plane. However, the thrust axis of each engine is not parallel to the x-axis. Each engine is canted out slightly (1.98°) so that the exit nozzles are closer to the airplane centerline than the front of the engines. The pitch or elevation angle of each engine is zero. Engine cant is measured by an azimuth angle \( \psi_{\text{eng}} \) that represents rotation about the body frame z-axis. Given this information, the body-axis components of thrust for each engine are computed as,

\[
\begin{align*}
TH_x; L &= TH_L \cos(\psi_{\text{eng}L}) \\
TH_y; L &= TH_L \sin(\psi_{\text{eng}L}) \\
TH_z; L &= 0 \\
TH_x; R &= TH_R \cos(\psi_{\text{eng}R}) \\
TH_y; R &= TH_R \sin(\psi_{\text{eng}R}) \\
TH_z; R &= 0
\end{align*}
\]

(6.6)

where the subscripts "L" and "R" denote left and right engines, and where,

\[
\psi_{\text{eng}L} = -1.98^\circ \quad \text{and} \quad \psi_{\text{eng}R} = 1.98^\circ
\]

(6.7)

The force quantities for the equations of motion can now be computed,

\[
\begin{align*}
F_{XE} &= TH_x; L + TH_x; R \\
F_{YE} &= TH_y; L + TH_y; R \\
F_{ZE} &= TH_z; L + TH_z; R
\end{align*}
\]

(6.8)

The engine thrust is assumed to be applied where the thrust axis intersects the "engine/airframe interface", defined in the engineering drawing, figure 3.1. As can be seen from figure 3.1, the location of the "engine/airframe interface" for the right engine is defined in the FS/BL/WL coordinate frame as (687.5, 18.9, 100.0). The interface point for the left engine is (687.5, -18.9, 100.0). This information is specified in the variables FSENG, BLENGR, BLENGL, and WLENG in CONSTANT statements in the fl8bas simulation. The vector that locates the engine/airframe interface point in the c.g.-centered body frame is computed in units of feet for use in calculating the moments about the c.g.,

\[
\begin{align*}
xe_{erf} &= -(FS_{\text{eng}} - FS_{\text{cg}}) / 12 \\
ye_{erf} &= (BL_{\text{eng}R} - BL_{\text{cg}}) / 12 \\
ye_{erf} &= (BL_{\text{eng}L} - BL_{\text{cg}}) / 12 \\
z_{erf} &= -(WL_{\text{eng}} - WL_{\text{cg}}) / 12
\end{align*}
\]

(6.9)

The calculations of (6.9) are performed once in the initialization phase of the simulation. Given this information, the moment quantities for the equations of motion can now be computed,

\[
\begin{align*}
M_{XE} &= -ze_{erf} F_{YE} + ye_{erf} TH_x; R + ye_{erf} TH_x; L \\
M_{YE} &= ze_{erf} F_{XE} - xe_{erf} F_{ZE} \\
M_{ZE} &= -(ye_{erf} TH_x; R + ye_{erf} TH_x; L) + xe_{erf} F_{YE}
\end{align*}
\]

(6.10)
7. SENSORS

The sensor code was taken from the LaRC real-time simulation (dmsf18). These models can also be found in subroutine FCSENS of the MDC simulation of the F/A-18. A table of sensor characteristics can be found in figure 7-7 of [MDC A7813, vol I, rev A, page 7-16] and selected parts are repeated below as Table 7.1. In the dmsf18 simulation, the sensor calculations and dynamics are performed in the same subroutines that model the control laws. In keeping with a policy of modeling all continuous dynamics in the derivative portion of the ACSL simulation, sensor MACRO's were written to implement the sensor models, and the sensor code was stripped out of the control law subroutines that are called from the FCS discrete block.

Table 7.1.a. Rate Gyro and Accelerometer Parameter Bounds

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Pitch/Yaw Rate Gyro</th>
<th>Roll Rate Gyro</th>
<th>Normal Accelerometer</th>
<th>Lateral Accelerometer</th>
</tr>
</thead>
<tbody>
<tr>
<td>Range</td>
<td>( \pm 60 , ^\circ/\text{sec} )</td>
<td>( \pm 300 , ^\circ/\text{sec} )</td>
<td>( \pm 10 , \text{g} )</td>
<td>( \pm 2 , \text{g} )</td>
</tr>
<tr>
<td>Threshold</td>
<td>.005 , ^\circ/\text{sec}</td>
<td>.01 , ^\circ/\text{sec}</td>
<td>.002 , \text{g}</td>
<td>.002 , \text{g}</td>
</tr>
<tr>
<td>Linearity</td>
<td>1% full scale</td>
<td>1% full scale</td>
<td>1% full scale</td>
<td>1% full scale</td>
</tr>
<tr>
<td>Null</td>
<td>.5 , ^\circ/\text{sec}</td>
<td>1.5 , ^\circ/\text{sec}</td>
<td>.05 , \text{g}</td>
<td>.01 , \text{g}</td>
</tr>
<tr>
<td>Hysteresis</td>
<td>.05 , ^\circ/\text{sec}</td>
<td>.30 , ^\circ/\text{sec}</td>
<td>.005 , \text{g}</td>
<td>.001 , \text{g}</td>
</tr>
<tr>
<td>Gradient Tolerance</td>
<td>( \pm 5 % )</td>
<td>( \pm 5 % )</td>
<td>( \pm 5 % )</td>
<td>( \pm 5 % )</td>
</tr>
</tbody>
</table>

Table 7.1.b. Pedal Force and Pressure Measurement Parameter Bounds

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Pedal Transducer</th>
<th>Static Pressure</th>
<th>Dynamic Pressure</th>
</tr>
</thead>
<tbody>
<tr>
<td>Range</td>
<td>( \pm 134 , \text{lbs} )</td>
<td>[0,38] in HG</td>
<td>[0,55] in HG</td>
</tr>
<tr>
<td>Threshold</td>
<td>.5 , \text{lbs}</td>
<td>.0005 in HG</td>
<td>.001 in HG</td>
</tr>
<tr>
<td>Linearity</td>
<td>2% full scale</td>
<td>incl in gradient tolerance</td>
<td>incl in gradient tolerance</td>
</tr>
<tr>
<td>Null</td>
<td>0.5% full scale</td>
<td>0.09 in HG</td>
<td>0.105 in HG</td>
</tr>
<tr>
<td>Hysteresis</td>
<td>1.0 lb (0 to 60 lbs)</td>
<td>incl in gradient tolerance</td>
<td>incl in gradient tolerance</td>
</tr>
<tr>
<td></td>
<td>4.0 lb (60 to 134 lbs)</td>
<td>incl in gradient tolerance</td>
<td>incl in gradient tolerance</td>
</tr>
<tr>
<td>Gradient Tolerance</td>
<td>( \pm 5 % )</td>
<td>( \pm 0.3 % )</td>
<td>( \pm 0.3 % )</td>
</tr>
</tbody>
</table>
The sensor outputs required by the subroutines that model the flight control laws are given in Table 7.2. The pedal force is an autonomous input to the simulation.

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Variable Name</th>
<th>Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\alpha_s$</td>
<td>ALFS</td>
<td>angle of attack, degrees</td>
</tr>
<tr>
<td>$n_y_s$</td>
<td>AYS</td>
<td>lateral acceleration, positive right, g's</td>
</tr>
<tr>
<td>$n_z_s$</td>
<td>AZS</td>
<td>vertical acceleration, positive up, g's</td>
</tr>
<tr>
<td>$p_s$</td>
<td>PS</td>
<td>body axis roll rate, °/sec</td>
</tr>
<tr>
<td>$q_s$</td>
<td>QS</td>
<td>body axis pitch rate, °/sec</td>
</tr>
<tr>
<td>$r_s$</td>
<td>RS</td>
<td>body axis yaw rate, °/sec</td>
</tr>
<tr>
<td>$Q_c_s$</td>
<td>QCIS</td>
<td>compressible impact pressure, PSF</td>
</tr>
<tr>
<td>$P_s$</td>
<td>PSTS</td>
<td>static pressure, PSF</td>
</tr>
</tbody>
</table>

The sensor values used by the flight control system model can be either the ideal values or values computed using various sensor models. The variable ISENS determines which type of sensor data is sent to the flight control subroutines. The ISENS variable was made integer type in order to accommodate multiple sensor models. The simulation currently calculates two sets of sensor outputs. The first set consists of the variables created by adding a "0" to the variable names in Table 7.2, i.e. \{ALFS0, AYS0, ..., PSTS0\}, and represents ideal sensors. The second set consists of the variables created by adding a "1" to the list in Table 7.2, i.e. \{ALFS1, AYS1, ..., PSTS1\}, and represents the sensor models used in the MDC simulation. At one time, a third, more complex, set of sensor models was implemented in the AGCB simulation to produce the variable set \{ALFS2, AYS2, ..., PSTS2\}. The ISENS=2 option was removed to reduce complexity and because it was not entirely integrated with the simulation trimming algorithm, but could be reinstalled if the need arose. The final output variables in Table 7.2 are determined from the sensor model sets according to the value of the integer switch, ISENS, as shown in Figure 7.1.

```
IF (ISENS=0) THEN
  ALFS = ALFS0
  PSTS = PSTS0
ELSE
  ALFS = ALFS1
  PSTS = PSTS1
END IF
```

Figure 7.1. Code block that selects sensor model
The sensor equations appear in both the initial section of the program code and in the derivative section. The initial section contains full code for the computations. The derivative section makes use of macros which appear at the top of the ACSL program as ACCEL1, ALGBT1, PITOT, and RGYRO1.

Ideal static pressure (PSTATC) is computed from the aircraft altitude (H, Height, in the main loop, HIC, Height Initial Condition, in the initial section) through the subroutine call to PSTAT. It interpolates for the static pressure value from an single independent variable (H) ATMAT62 data table. Ideal compressible impact pressure (QC) is computed from the ideal static pressure (PSTATC) and the Mach number (MACH, for main loop, MACHTR, MACH TRim, for the initial section) through the subroutine CPRESS. It interpolates for the compressible impact pressure from a two independent variable (MACH and PSTATC) data table.

Sensed static pressure (STS1, ISENS = 1) is computed from the ideal pressure divided by a scaling factor, SPSFXD. SPSFXD is computed as a function of Mach number and sensed angle of attack (ALFS1). The QCDA,QCDB...QCDH variables which appear in the scaling equation are a function of Mach number and are defined as constants in the initial section of the program code. The sensed compressible pressure (QCIS1, ISENS=1) is also determined as a function of Mach and angle of attack, where the static pressure is added to the ideal compressible pressure before the computation and then removed afterwards. A final computation is then made based on a limited angle of attack. These computations model the Pitot tube and static probe mechanics, where the measured value, as determined by pressure differentials, does not exactly reflect the true air pressure values. These pressure values are used in the flight control system for air data scheduling. The air data scheduled gain values were designed to be scheduled from measured pressure values and not the true or ideal pressures.

Sensed angle of attack is computed from the true angle of attack with a gain and bias based on air flow. The bias, (ALFB), is determined by the landing gear position, if the landing gear is retracted (the normal position for any runs) ALFB=1.9, extended ALFB=1.2. The gain, GKAOA, (where it is divided into the true alpha minus the bias) is a function of the Mach number. The measured angle of attack is limited to -14 and 56 degrees.

7.1 Ideal Static Pressure and Compressible Impact Pressure

Static pressure, $P_S$, is calculated as a function of altitude in feet by the subroutine PSTAT. The function,

$$P_S, \text{ lbs/ft}^2 = F_{PSTAT}(H)$$

implemented in subroutine PSTAT is plotted in figure 7.2.
Subroutine CPRESS calculates compressible dynamic pressure as a function of Mach and static pressure, $P_S$, as follows:

$$Q_C = \left(\frac{Q_C}{P_S}\right) P_S$$

where the ratio $Q_C/P_S$ is a function of Mach number and is given by figure 7.3. The subroutines PSTAT and CPRESS are called from the DERIVATIVE block.
7.2 Ideal Sensor Set (ISENS=0)

\[ \alpha_{s0} = \alpha, \text{ degrees} \]
\[ n_{ys0} = n_y, \text{ g's} \]
\[ n_{zs0} = -n_z - 1, \text{ g's} \]
\[ p_{s0} = (180/\pi)p, \text{ /sec} \]
\[ q_{s0} = (180/\pi)q, \text{ /sec} \]
\[ r_{s0} = (180/\pi)r, \text{ /sec} \]
\[ Q_{cs0} = Q_c, \text{ PSF} \]
\[ P_{Ss0} = P_S, \text{ PSF} \]

where,

\[ n_y = \frac{\dot{v} + ru - pw - gl_{yz}}{g} \]
\[ n_z = \frac{\dot{w} + pv - qu - gl_{zz}}{g} \]

7.3 Accelerometers (ISENS=1)

The calculations for the lateral and vertical accelerometers are performed in the macro ACCEL1. The lateral accelerometer output, AYS1, is positive for an acceleration to the right and the vertical accelerometer output, AZS1, is positive for an upward acceleration. Both AYS1 and AZS1 have units of g's. Lever arm effects are calculated and the 1 g bias removed from AZS1. Both outputs are bounded according to Table 7.1.a. Hysteresis, bias, quantization and misalignment are not modeled in the MDC sensor set. The MDC simulation, mdcfl8, has comments that refer to a transfer function of \[ G(s) = \frac{1}{(s/220)+1} \] that approximates the accelerometer dynamics, but was deleted from the MDC simulation. The f18bas simulation does not model accelerometer dynamics either. The location of the accelerometers in the body frame in feet is given by,

\[ x_a = -(FS_a - FS_{cg}) / 12. \]
\[ y_a = (BL_a - BL_{cg}) / 12. \]
\[ z_a = -(WL_a - WL_{cg}) / 12. \]
where \( x_a, y_a, z_a \) represent distances in feet forward from the c.g., right of the c.g. and below the c.g., respectively, and where,

\[
\begin{align*}
F_{S_{cg}} &= F_{SCG}, \text{ Fuselage Station c.g.} = 455.0 \text{ inches} \\
B_{L_{cg}} &= B_{LCG}, \text{ Buttock Line c.g.} = 0.0 \text{ inches} \\
W_{L_{cg}} &= W_{LCG}, \text{ Water Line c.g.} = 102.8 \text{ inches} \\
F_{S_{a}} &= NYLOC(1) = 306.75 \text{ inches} \\
B_{L_{a}} &= NYLOC(2) = 10.5 \text{ inches} \\
W_{L_{a}} &= NYLOC(3) = 91.3 \text{ inches}
\end{align*}
\]

The lateral and vertical accelerations with lever arm effects included and 1 g bias removed are,

\[
\begin{align*}
\dot{n}_y &= n_y + \frac{(pq + r)x_a - (p^2 + r^2)y_a + (qr - p)z_a}{g} \\
\dot{n}_z &= -1 - n_z - \frac{(pr - q)x_a + (qr + p)y_a - (p^2 + q^2)z_a}{g}
\end{align*}
\]

The ISENS=1 output accelerations are bounded according to table 7-1a.

\[
\begin{align*}
\dot{n}_y &= n_y \left(2\right) \\
\dot{n}_z &= n_z \left(10\right)
\end{align*}
\]

### 7.4 Rate Gyros (ISENS=1)

The outputs of the rate gyro's are simply the body frame roll, pitch, and yaw rates in units of degrees/sec with limits applied as indicated in table 7.1a. The calculations are performed in macro RGYRO1 as follows,

\[
\begin{align*}
\dot{\rho}_1 &= \left(\frac{180}{\pi}\right) \left(\frac{300}{300}\right) \text{ °/sec} \\
\dot{q}_1 &= \left(\frac{180}{\pi}\right) \left(\frac{60}{60}\right) \text{ °/sec} \\
\dot{r}_1 &= \left(\frac{180}{\pi}\right) \left(\frac{60}{60}\right) \text{ °/sec}
\end{align*}
\]
7.5 Angle of Attack Measurement (ISENS=1)

The angle-of-attack probe model is implemented in macro ALFBT1. The "probe" quantity is calculated by passing the angle of attack at the c.g. through a filter representing the probe dynamics,

\[
\alpha_p = \left( \frac{1}{0.073 \ s + 1} \right) \alpha
\]

The local probe angle of attack is adjusted for the induced upwash due to pitch rate,

\[
\alpha_{p1} = \alpha_p - \frac{(180/\pi) \ I_p q}{\sqrt{V}}
\]

where \( I_p = 24 \) feet. From purely geometric consideration, one would expect \( I_p \) to be the distance from the center-of-gravity to the angle-of-attack probe where \( I_p \) has units of feet and is positive if the probe is forward of the c.g. A probe located at a fuselage station (FS) of 167 inches is consistent with \( I_p = 288 \) inches and a nominal c.g. location of \( F_{scg} = 455.0 \) inches, placing the probe between the nose (FS=60.50) and the leading edge of the cockpit (FS=188.0) (see figure 3.1). However, one must wonder why the probe dynamics are not applied to the total local measurement that includes pitch rate effects instead of to the angle of attack at the c.g. At this point, the only answer is that this is the way it is done in subroutine FCSENS of the MDC simulation.

An angle-of-attack probe bias and gain inverse are calculated. The bias is given by,

\[
\alpha_{pbias} = \begin{cases} 
1.9 \text{ degrees if gear up} \\
1.2 \text{ degrees if gear down.}
\end{cases}
\]

The gain inverse is a function of limited Mach number,

\[
GK_\alpha = FGKAOA(M^{1.4} \ I_p^{1.9})
\]

where the function \( FGKAOA \) is defined by figure 7.4.

The final limited sensor output is then,

\[
\alpha_{s1} = \frac{\alpha_{p1} - \alpha_{pbias}}{GK_\alpha} \left[ \begin{array}{c} 56 \\ -14 \end{array} \right] \quad (ALFS1)
\]
The calculation of indicated static pressure and indicated compressible dynamic pressure requires eight parameters, QCDx, where x={A,B,...,H}. The QCDx are 21 element arrays and the current value for each QCDx parameter is determined as a tabular function of Mach. XHM1 is the similarly sized independent variable array of Mach numbers with a maximum value of 1.65 and a minimum of 0. A search is performed to determine the integer IXHM such that \( XHM1(IXHM) \leq \text{Mach} < XHM1(IXHM+1) \). The IXHM\( ^{th} \) elements of the QCDx arrays are used in the following calculations. No interpolation is done on the QCDx variables. In the notation below, QCDx = QCDx(IXHM). The QCDx parameters as functions of Mach are plotted in figure 7.5.a-h.

The calculation of the sensed static pressure for ISENS=1, PS\( _{S1} \), is shown in equations 7.1 through 7.3.

\[
S_{PSFXD} = 1.0 - Q_{CDBM} - Q_{CDA} - (Q_{CDBM} + Q_{CDC})\alpha_{s1} \tag{7.1}
\]

\[
P_{S_{S1}} = P_S / S_{PSFXD} \tag{7.2}
\]

\[
PTS_{1} = P_{S_{S1}} \tag{7.3}
\]

The calculation of indicated compressible dynamic pressure is shown in equations 7.4 through 7.8.

\[
P_T = Q_c + P_S \tag{7.4}
\]

\[
P_{T1} = \frac{P_T}{1.0 - Q_{CDFM} - Q_{CDE} - (Q_{CDH} + Q_{CDG})\alpha_{s1}} \tag{7.5}
\]
An uncorrected initial value for indicated compressible dynamic pressure is calculated as follows,

\[ Q_{c_1} = P_{TI} + P_{S_1} \]  

(7.6)

The initial value for indicated compressible dynamic pressure is then adjusted for angle-of-attack effects per MDC memo 341-6241 dated "23Feb81".

\[ Q_{c_{s1}} = Q_{c_1} \left(1 - (0.04 \alpha \left[ \frac{55}{30} - 30 \right])^2 \right) \]  

(7.7)

\[ QCIS1 = Q_{c_{s1}} \]  

(7.8)
Figure 7.5. e QCDE = f(Mach)

Figure 7.5. f QCDF = f(Mach)

Figure 7.5. g QCDG = f(Mach)

Figure 7.5. h QCDH = f(Mach)
8. ACTUATORS

The simulation described herein includes dynamic models for the following control surfaces,

(1) stabilators (right and left),
(2) rudders (right and left),
(3) ailerons (right and left),
(4) trailing-edge flaps (right and left),
(5) leading-edge flaps (right and left),
(6) speed brake, and
(7) thrust vectoring vanes (2 per engine, 4 total).

The stabilators, rudders, ailerons, trailing-edge, and leading-edge flaps are hydraulically powered and are referred to in both MDC documents and this report as the primary controls. The single speed brake is positioned between and forward of the vertical fins and is driven at a constant rate of 24 degrees per second. The lower and upper limits of the speed brake deflection are 0° and 60°. The primary controls and the speed brake are found on the basic F/A-18 airframe.

The thrust vectoring vane actuation systems modeled in this simulation reflect a preliminary design of the thrust vectoring system installed on the F-18/HARV and do not agree with the final installation. The documentation of the final system will be undertaken in a separate report. The thrust vectoring vanes are each modeled as first order transfer functions with a steady state gain of one, a time constant of (1/30) seconds, rate limits of 80 °/s and position limits of +/- 30°.

8.1 Linear Dynamics - Primary Controls

The actuation systems for the primary controls in their normal mode of operation are discussed in detail in pages 6-1 through 6-40 of MDC A7813, vol II. The servo loop block diagrams for the primary controls are given in figures 6-2, 6-4, 6-6, 6-8 and 6-10 of MDC A7813, vol II. These block diagrams are repeated in a simplified form in this document as figures 8.1 through 8.5. The high order models represented in these figures describe main ram response with external load.

The transfer functions for the five primary actuators (stabilator, rudder, aileron, leading-edge flaps, and trailing-edge flaps) are presented in Table 8.1 through 8.5. Each table contains three transfer function models of the corresponding actuator type; (a) a high order model; (b) an intermediate order model; and (c) a low order model. For each actuator type, transfer function (a) is derived from the high order block diagrams in figures 8.1 through 8.5. Transfer functions (b) are discussed in pages 6-18 through 6-24 of MDC A7813, vol II. The (b) transfer functions are second order for all except the stabilators, which are fourth order. Transfer functions (c) consists of the lowest order models, the first order transfer functions that are used in both the MDC simulation code and the DMS real-time simulation at LaRC. The (a) transfer functions can be realized by linearizing the nonlinear block diagrams of figures 8.1 to 8.5. Comparisons of gain and phase response of the (a), (b), and (c) transfer functions for the primary controls are shown in figures 8.6 through 8.10. The low order models agree pretty well in phase with the intermediate and high order models out to about 10 radians/second.

An initial form of the ACSL simulation included elastic dynamics (see section 1.2), and in that simulation the (b) transfer functions were implemented. When the elastic dynamics were removed and time histories were compared with results generated by the DMS simulation, significant differences in aircraft responses due to pilot pitch and yaw doublets resulted. These differences were much reduced when the stabilator and rudder actuator models were changed to the first order models. The ACSL simulation now uses the first order actuator models.
Figure 8.1. Stabilator Servoactuator Block Diagram
Figure 8.2. Rudder Servoactuator Block Diagram

Figure 8.3. Aileron Servoactuator Block Diagram
Figure 8.4. Trailing-Edge Flaps Servoactuator Block Diagram
Figure 8.5. Leading-edge flaps Servoactuator Block Diagram
### Table 8.1. Linear Stabilator Actuator Models - $\frac{\delta(s)}{\delta_c(s)}$

\[
\frac{\left(\frac{s}{81.7}^2 + 2(0.07)\left(\frac{s}{81.7}\right) + 1\right)}{\left(\frac{s}{37.7}^2 + 2(0.359)\left(\frac{s}{37.7}\right) + 1\right)} \cdot \frac{\left(\frac{s}{143}^2 + 2(0.637)\left(\frac{s}{143}\right) + 1\right)}{\left(\frac{s}{351}^2 + 2(0.84)\left(\frac{s}{351}\right) + 1\right)} \cdot \frac{\frac{s}{284} + 1}{\frac{s}{808} + 1} \cdot \frac{\frac{s}{404} + 1}{\frac{s}{1098} + 1} \quad (a)
\]

\[
\frac{\left(\frac{s}{82.9}^2 + 2(0.068)\left(\frac{s}{82.9}\right) + 1\right)}{\left(\frac{s}{36.4}^2 + 2(0.41)\left(\frac{s}{36.4}\right) + 1\right)} \cdot \frac{\left(\frac{s}{105.3}^2 + 2(0.59)\left(\frac{s}{105.3}\right) + 1\right)}{\left(\frac{s}{30} + 1\right)} \quad (b)
\]

\[
\frac{1}{\left(\frac{s}{30} + 1\right)} \quad (c)
\]

### Table 8.2. Linear Rudder Actuator Models - $\frac{\delta(s)}{\delta_c(s)}$

\[
\frac{\left(\frac{s}{357} + 1\right)}{\left(\frac{s}{61.9} + 1\right)} \cdot \frac{\left(\frac{s}{131} + 1\right)}{\left(\frac{s}{543}^2 + 2(0.997)\left(\frac{s}{543}\right) + 1\right)} \quad (a)
\]

\[
\frac{1}{\left(\frac{s}{72.1}^2 + 2(0.69)\left(\frac{s}{72.1}\right) + 1\right)} \quad (b)
\]

\[
\frac{1}{\left(\frac{s}{48} + 1\right)} \quad (c)
\]

### Table 8.3. Linear Aileron Actuator Models - $\frac{\delta(s)}{\delta_c(s)}$

\[
\frac{(0.993)\left(\frac{s}{556} + 1\right)}{\left(\frac{s}{103}^2 + 2(0.810)\left(\frac{s}{103}\right) + 1\right)} \cdot \frac{(0.494)\left(\frac{s}{494} + 1\right)}{\left(\frac{s}{759}^2 + 2(0.789)\left(\frac{s}{759}\right) + 1\right)} \cdot \frac{\left(\frac{s}{75}^2 + 2(0.59)\left(\frac{s}{75}\right) + 1\right)}{\left(\frac{s}{48} + 1\right)} \quad (a)
\]

\[
\frac{1}{\left(\frac{s}{75}^2 + 2(0.59)\left(\frac{s}{75}\right) + 1\right)} \quad (b)
\]

\[
\frac{1}{\left(\frac{s}{48} + 1\right)} \quad (c)
\]
Table 8.4. Linear Trailing-Edge Flap Actuator Models - \( \frac{\delta(s)}{\delta_c(s)} \)

\[
\frac{1.134 \left( \frac{s}{284} + 1 \right) \left( \frac{s}{808} + 1 \right)}{(\frac{s}{33.4} + 1) (\frac{s}{60.6} + 1) \left( (\frac{s}{314})^2 + 2(0.956)(\frac{s}{314}) + 1 \right) (\frac{s}{447} + 1) \left( \frac{s}{1045} + 1 \right)}
\]

(a)

\[
\frac{1}{(\frac{s}{35})^2 + 2(0.71)(\frac{s}{35}) + 1}
\]

(b)

\[
\frac{1}{(\frac{s}{20}) + 1}
\]

(c)

Table 8.5. Linear Leading-Edge Flap Actuator Models - \( \frac{\delta(s)}{\delta_c(s)} \)

\[
\frac{\left( \frac{s}{283} + 1 \right) \left( \frac{s}{808} + 1 \right)}{(\frac{s}{34} + 1) (\frac{s}{58.5} + 1) \left( (\frac{s}{281})^2 + 2(0.980)(\frac{s}{281}) + 1 \right) (\frac{s}{680} + 1)}
\]

(a)

\[
\frac{1}{(\frac{s}{26.9} + 1) (\frac{s}{82.9} + 1)}
\]

(b)

\[
\frac{1}{(\frac{s}{20}) + 1}
\]

(c)
Figure 8.6. Gain and phase response of the (a), (b) and (c) transfer functions for the stabilator
Figure 8.7. Gain and phase response of the (a), (b) and (c) transfer functions for the rudder
Figure 8.8. Gain and phase response of the (a), (b) and (c) transfer functions for the aileron
Figure 8.9. Gain and phase response of the (a), (b) and (c) transfer functions for the trailing-edge flaps
Figure 8.10. Gain and phase response of the (a), (b) and (c) transfer functions for the leading-edge flaps
8.2 Nonlinearities - Primary Controls

The significant nonlinearities in the actuators include a minimum resolution in the digital command due to 12 bit digital-to-analog conversion, hydromechanical thresholds, rate limiting, and nonlinear gearing. The first three of these types of nonlinearities are given in Table 6.2.1-1 of MDC A7813, vol II, and are repeated in Table 8.6 below.

Table 8.6. Actuator Nonlinearities

<table>
<thead>
<tr>
<th>Actuator</th>
<th>Minimum Digital Command (degrees)</th>
<th>Threshold (fraction of full)</th>
<th>No Load Rate Limit (degrees/second)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Stabilator</td>
<td>0.0083</td>
<td>0.10</td>
<td>40</td>
</tr>
<tr>
<td>Rudder</td>
<td>0.0146</td>
<td>0.05</td>
<td>56</td>
</tr>
<tr>
<td>Aileron</td>
<td>0.022</td>
<td>0.05</td>
<td>100</td>
</tr>
<tr>
<td>Trailing-Edge Flaps</td>
<td>0.0127</td>
<td>0.05</td>
<td>18</td>
</tr>
<tr>
<td>Leading-Edge Flaps</td>
<td>0.0106</td>
<td>0.15</td>
<td>18</td>
</tr>
</tbody>
</table>

The main ram slewing rate limit is proportional to \((P_S - P_1)^{1/2}\), where \(P_S\) is the supply pressure (3000 PSI) and \(P_1\) is the pressure on the resisting side of the piston due to external load. The maximum slewing rate occurs when \(P_1\) is zero. When \(P_1\) equals \(P_S\), the actuator stalls.

In the ACSL simulation, of the possible nonlinear effects, only the no load rate limits are modeled. In both the MDC simulation and the DMS simulation, the no load rate limit used for the rudder actuators is 61 degrees/second instead of 56 degrees/second as shown in Table 8.6. Another set of specifications for actuator models can be found on page 12 of MDC report A8449 and is repeated below as Table 8.7. The no load rate limit for the rudder actuators is given as 61 degrees/second in Table 8.7. The 61 degree/second limit is used in the f18bas simulation.

Table 8.7. MDC F/A-18 Flight Hardware Integration Simulator

<table>
<thead>
<tr>
<th>Actuator</th>
<th>Rate Limit</th>
<th>Position Limit</th>
<th>Mechanization</th>
</tr>
</thead>
<tbody>
<tr>
<td>Stabilator</td>
<td>+/- 40°/s</td>
<td>-24°, +10.5°</td>
<td>1st order lag, (\tau = 1/30) s</td>
</tr>
<tr>
<td>Rudder</td>
<td>+/- 61°/s</td>
<td>-30°, +30°</td>
<td>1st order lag, (\tau = 1/40) s</td>
</tr>
<tr>
<td>Aileron</td>
<td>+/- 100°/s</td>
<td>-25°, +45°</td>
<td>1st order lag, (\tau = 1/48) s</td>
</tr>
<tr>
<td>Trailing-Edge Flaps</td>
<td>+/- 18°/s</td>
<td>-8°, +45°</td>
<td>1st order lag, (\tau = 1/20) s</td>
</tr>
<tr>
<td>Leading-Edge Flaps</td>
<td>+/- 18°/s</td>
<td>-3°, +34°</td>
<td>1st order lag, (\tau = 1/20) s</td>
</tr>
</tbody>
</table>

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For further discussion of gearing nonlinearities and plots of the effect of hinge moment on maximum actuator rate, the reader is referred to section 6.2 of MDC report A7813, vol II.

8.3 Speedbrake

The speedbrake system is described in section 8.7 of MDC A7813, vol I, Rev A. The speedbrake actuator is operated by a selector valve which ports hydraulic pressure to the main ram for extension or retraction. The selector valve is electrically controlled by a three position switch, OFF, RETRACT, and EXTEND, on the right hand throttle. The EXTEND position is a momentary. The OFF command holds the speedbrake in its current position. When the speedbrake is fully retracted, both "OFF" and "RETRACT" switch positions command the selector valve to the retract position.

The speedbrake rate is controlled by a flow regulator and restrictor. "The speedbrake extension time is limited to 2.5 seconds or approximately 20 degrees to 30 degrees per second (no load)" [MDC A7813, p8-14]. Maximum surface deflection is 60 degrees. In the f18bas simulation, the speedbrake no-load rate limit, SBNLRL, has been set to 60/2.5 = 24 °/s. No provision is made for reduced rate due to aerodynamic hinge moment. The maximum driving hinge moment available at 60 degrees open with the full 3000 psi of hydraulic pressure available is 296,000 in-lbs.

8.4 Thrust Vectoring Vane Actuators

The four actuators in the preliminary vane actuation system are each modeled with first order lag transfer functions with a time constant of 0.05 seconds, a rate limit of 80 °/sec, and position limits of +/- 30°. Again, this vane configuration of two vanes per nozzle is a preliminary version. The actual system implemented on the HARV F18 has three vanes per nozzle.
9. FLIGHT CONTROL SYSTEM (FCS)

The fI8bas simulation implements the Control Augmentation System (CAS) of the inner loop F/A-18 Flight Control System defined by the 8.3.3 production programmable read-only memory (PROM) set. The theory of operation and design considerations of the CAS is described in section 9.1. The implementation issues associated with the fI8bas simulation (as opposed to the actual aircraft) are discussed in section 9.2.

9.1 FCS Theory of Operation

The inner loop flight control law theory of operation for the F/A-18 is described in detail in section 16 of MDC report A7813, Vol I, rev A and section 1 of MDC report A4107, vol I, rev J. The inner loop control laws are divided into three channels: longitudinal, lateral, and directional. A preliminary thrust vectoring option (LTHVEC=T.) exists in the code wherein additional pitch and yaw commands are generated by the control laws for use by the mixer/predictor. The mixer/predictor resolves the pitch and yaw command into actual vane commands for proposed thrust vectoring hardware. As indicated in section 1.2 of this report, the thrust vectoring option in the fI8bas simulation represents a preliminary design version that has been superseded and will not be described in this document.

The inner loop CAS is a multi-rate digital controller. The actual flight computers update at a rate of 160 Hz. The inner loop calculations are performed at alternate frames of the flight control computer, so that the fastest inner loop of any of the controllers is 80 Hz. The details of the control law discretization can be found in MDC report A4107, vol I, rev J. All the sampling rates are fast enough that the continuous description offered here will suffice for analysis.

9.1.1 Longitudinal Auto Flap Up CAS

Three modes of leading-edge and trailing-edge flap management are performed in the pitch inner loop control laws of the F/A-18: (1) auto flap up (AFU), (2) half flaps, and (3) full flaps. The AFU mode is for up and away flight. The half and full flap settings are used in take-off and landing, respectively. In the fI8bas simulation, only the auto flap up mode is supported. A block diagram of the pitch inner-loop control augmentation system in the AFU mode is presented in figure 9.1 (a-d). Figure 9.1 is a simplified version of "FIG 1/OFP V10.1" on page 1-13 of MDC report A4107, vol I, rev J. Paths in "FIG 1/OFP V10.1" having to do with outer loops, the direct electric link (DEL) reversion mode, and HALF and FULL flap management modes have been deleted. Also omitted from figure 9.1 are blocks defining stick dynamics, trim functions, and the g-limiter logic. The definition of the pitch gains (PKxx) in terms of pitch functions (FUNxx) are given in table 9.1. Table 9.2 defines the longitudinal filters used in figure 9.1. The pitch functions required to define quantities in both tables 9.1 and 9.2 are defined in figure 9.2 (a-o). The following quote is taken from pages 1-2 through 1-4 of MDC report A4107, Vol I, REV. J. Italics are comments inserted by the authors. Grammatical hyphens have been added.

Primary control of the F/A-18 aircraft longitudinal motions is accomplished through the CAS. The Direct Electric Link (DEL) and mechanical system provide backup for the pitch CAS. Management of the leading and trailing edge flaps is provided through the use of a cockpit switch which calls for either AUTO, HALF, or FULL flaps. A block diagram of the longitudinal control system is presented in Figure 1 (figure 9.1 of this document). Longitudinal functions and logic diagrams are given in Figure 1.1 through 1.44 (figure 9.2 of this document). Longitudinal digital filter characteristics are summarized in Table 1-1 (Table 9.2 of this document).
Auto Flap Up (CAS On) - The pitch CAS uses a pilot commanded longitudinal stick position input as a command to the CAS. The forward path gain is air data scheduled (Function 32A) to yield a uniform initial pitch acceleration response for sharp inputs. The CAS feedback parameters are a blend of air data scheduled pitch rate (Functions 40 and 68), normal acceleration, and angle of attack. Pitch rate and normal acceleration feedbacks give improved pitch dynamic characteristics and load factor control in the mid to high dynamic pressure portion of the flight envelope. Air combat maneuvering characteristics and increased stick-force-per-g cues in the low to mid dynamic pressure flight regime are provided by the air data scheduled pitch rate feedback. Angle-of-attack feedback provides additional increased stick force cues for low speed high angle-of-attack air combat maneuvering. Roll rate multiplied by yaw rate is fed to the longitudinal control system (Function 107) to reduce the effects of inertial coupling.

The pilot commanded stick position, pitch rate, normal acceleration, and angle-of-attack feedback signals are iterated at the rates shown in Figure 1 (figure 9.1 of this document).

The pitch CAS forward path is comprised of an air data scheduled gain (Function 32A), a forward loop integrator, and the stabilator servo and power cylinder. The aircraft response (feedback) is compared to the maneuver command; the resulting difference drives the servo/power cylinder to reduce the maneuver error to zero through the forward loop integrator. Consequently, the aircraft is automatically kept in steady state trim (hands off) since any aircraft normal acceleration different from the commanded normal acceleration is reduced to zero by the action of the integrator.

The notch structural filter located in the feedback paths attenuates any undesirable motions which are sensed by the motion sensors due to aeroelastic bending of the aircraft structure. The longitudinal forward loop gain (Functions 32A) and pitch rate feedback gains (Functions 40 and 68) are scheduled with air data. A supersonic (air data scheduled time constant, Function 22) lead-lag filter is employed in the pitch rate feedback path. The forward loop integrator gain is air data scheduled (Function 12) and angle-of-attack activated (AOA less than 33 degrees). This implementation is necessary to maintain adequate loop gain margins, phase margins, and handling qualities throughout the flight envelope. Scheduling pitch rate feedback gain with air data results in increased feedback gain with decreasing dynamic pressure or increasing altitude. This increases the stick force cues for mid to low speed flight conditions and provides a pitch attitude type of control law for tracking since pitch rate feedback is nulled via the forward loop integrator.

The stall margin network introduces an aircraft nose-down command proportional to angle of attack (AOA) above 22 degrees AOA. The effect of the stall margin portion of the control laws is to increase the stick force cues for high angle-of-attack maneuvering.

A speedbrake-to-stabilator interconnect (Function 100) is incorporated to alleviate g transients for speedbrake extension/retraction. The interconnect command is on/off in response to speedbrake solenoid valve command. The magnitude of the input command is air data scheduled. The interconnect command is lagged through a first order low-pass filter with the time constant scheduled with air data and as a function of speedbrake extension or retraction. The speedbrake extend time constant is less than the speedbrake retract time constant.

Flap Control - Auto Flap UP - With the flap switch in AUTO, the leading and trailing edge maneuvering flaps are scheduled with angle of attack and air data (Functions 24 and 27) to optimize performance, to improve the high angle of attack characteristics, and provide load alleviation at elevated g's. Flap position limits are computed as a function of air data inputs (Functions 25, 28 and 29) to prevent the application of excessive air loads on the flaps.
Figure 9.1. Longitudinal CAS - (a) Main feedback paths
Figure 9.1. Continued - (b) Feedforward integrator
Figure 9.1. Continued - (c) Flap command and inertial compensation logic
Figure 9.1. Concluded - (d) Stabilator command synthesis
Table 9.1. Pitch gains in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Function</th>
<th>AFU Mode</th>
<th>Spin Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>PK3</td>
<td>F12*F32A + F116</td>
<td>0.0</td>
</tr>
<tr>
<td>PK4</td>
<td>1.5*F32A</td>
<td>0.0</td>
</tr>
<tr>
<td>PK5</td>
<td>F32A</td>
<td>0.7</td>
</tr>
<tr>
<td>PK6</td>
<td>3.5*F32A</td>
<td>0.0</td>
</tr>
<tr>
<td>PK7</td>
<td>F32A</td>
<td>0.0</td>
</tr>
<tr>
<td>PK8</td>
<td>F68*F32A + F40</td>
<td>0.0</td>
</tr>
<tr>
<td>PK9</td>
<td>8.5*F32A + F12</td>
<td>0.0</td>
</tr>
<tr>
<td>PK10</td>
<td>1.0</td>
<td>0.0</td>
</tr>
<tr>
<td>PK11</td>
<td>F68*F32A + F12</td>
<td>0.0</td>
</tr>
<tr>
<td>PK12</td>
<td>F32A*F12</td>
<td>0.0</td>
</tr>
<tr>
<td>PK13</td>
<td>-22.0</td>
<td>NA by virtue of PK17</td>
</tr>
<tr>
<td>PK14</td>
<td>0.0</td>
<td>0.1</td>
</tr>
<tr>
<td>PK15</td>
<td>F107</td>
<td>0.0</td>
</tr>
</tbody>
</table>

Table 9.2. Pitch filters in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Filter</th>
<th>Transfer Function</th>
<th>Where Used</th>
</tr>
</thead>
<tbody>
<tr>
<td>P2</td>
<td>( \frac{\tau_N s + 1}{\tau_D s + 1} )</td>
<td>( \tau_N = 0.015(1 + \text{FUN22}) )</td>
</tr>
<tr>
<td></td>
<td>( \tau_D = 0.015 )</td>
<td>Pitch Rate</td>
</tr>
<tr>
<td>P5</td>
<td>( \frac{1}{\tau_D s + 1} )</td>
<td>( \tau_D = 0.04 )</td>
</tr>
<tr>
<td></td>
<td>Normal Acceleration</td>
<td></td>
</tr>
<tr>
<td>P8</td>
<td>( \frac{(s/\omega)^2 + 2\zeta_N(s/\omega) + 1}{(s/\omega)^2 + 2\zeta_D(s/\omega) + 1} )</td>
<td>( \zeta_N = 0.03 )</td>
</tr>
<tr>
<td></td>
<td>( \zeta_D = 0.70 )</td>
<td>Notch</td>
</tr>
<tr>
<td></td>
<td>( \omega = 60.0 , \text{r} / \text{s} )</td>
<td></td>
</tr>
<tr>
<td>P11</td>
<td>( \frac{1}{\tau_D s + 1} )</td>
<td>( \tau_D = 0.39 )</td>
</tr>
<tr>
<td></td>
<td>Leading-Edge Flaps</td>
<td></td>
</tr>
<tr>
<td>P12</td>
<td>( \frac{1}{\tau_D s + 1} )</td>
<td>( \tau_D = 0.79 )</td>
</tr>
<tr>
<td></td>
<td>Trailing-Edge Flaps</td>
<td></td>
</tr>
<tr>
<td>P15</td>
<td>( \frac{1}{\tau_D s + 1} )</td>
<td>0.49 &lt; ( \tau_D ) &lt; 2.0 for retraction</td>
</tr>
<tr>
<td></td>
<td>Speed brake</td>
<td></td>
</tr>
<tr>
<td>P16</td>
<td>( \frac{1}{\tau_D s + 1} )</td>
<td>( \tau_D = 0.174 )</td>
</tr>
<tr>
<td></td>
<td>NZAF</td>
<td></td>
</tr>
</tbody>
</table>

89
(a) Pitch function 12 - Pitch forward loop integrator gain schedule
Auto Flap Up ($R_i, P_s$)

(b) Pitch function 20 - Pitch stick gradient

Figure 9.2 Pitch CAS Functions
(c) Pitch function 22 - Fader on the supersonic compensation

Auto Flap Up (α, R_i)

(d) Pitch function 24 - Trailing-edge flap schedule

Auto Flap Up (Q_c)

Figure 9.2 Continued.
(e) Pitch function 25 - Trailing-edge flap schedule
Auto Flap Up ($Q_C$)

(f) Pitch function 27 - Leading-edge flap schedule
Auto Flap Up ($\alpha$, $R_i$)

Figure 9.2 Continued.
(g) Pitch function 28 - Leading-edge flap schedule
Auto Flap Up (Q_c)

(F29U) (Upper limit)

(Mach = 0.93) (0.7, 34)

(F29L) (Lower limit)

P_s < 1200 PSF

(Mach = 1.15) (1.146, 0.0)

(h) Pitch function 29 - Leading-edge flap schedule
Auto Flap Up (R_i)

Figure 9.2 Continued.
(i) Pitch function 32A - Longitudinal forward loop gain schedule
Auto Flap Up (Qc)

(j) Pitch function 40 - Pitch rate feedback gain schedule
Auto Flap Up (Ps, Qc, Ri, STORES)

Figure 9.2 Continued.
(k) Pitch function 68 - Pitch rate feedback gain schedule
Auto Flap Up ($Q_c$)

(l) Pitch function 107 - Longitudinal inertial gain schedule
Auto Flap Up ($Q_c$)

Figure 9.2 Continued.
(m) Pitch function 115 - Longitudinal nonlinear stick gradient
Auto Flap Up (Qc)

(n) Pitch function 116 - Pitch nonlinear integrator gain schedule
Auto Flap Up (Rj, P5)

Figure 9.2 Continued.
(o) Pitch function 117 - Nonlinear stick command gain
Auto Flap Up ($Q_c$)

Figure 9.2 Concluded.
Lateral Auto Flap Up CAS

Figure 9.3 (a-d) is a simplified version of the diagram "Figure 2 / OFP V10.1" on page 1-69 of MDC report A4107, Vol I, REV. J. Paths having to do with outer loops and the direct electric link (DEL) reversion mode have been deleted. The definition of the lateral gains (RKxx) in terms of roll functions (FUNxx) are given in Table 9.3. Table 9.4 defines the lateral filters used in figure 9.3. The roll functions required to define quantities in both tables 9.3 and 9.4 are defined in figure 9.4 (a-l). The following quote is from pages 1-65, 1-97 of MDC report A4107, Vol I, REV. J. Italics are comments inserted by the authors. Grammatical hyphens have been added.

Lateral control is accomplished by a control-by-wire system which commands the ailerons, differential stablators, differential trailing-edge flaps, and differential leading-edge flaps. The controls consist of Control Augmentation System (CAS) and Digital and Analog Direct Electric Link (DEL) functions. A block diagram of the lateral control system is shown in Figure 2 (Figure 9.3 of this report). Lateral functions and logic diagram are presented in Figure 2.1 through 2.20 (Figure 9.4 of this report). Lateral digital filter characteristics are summarized in Table 1-3 (Table 9.4 of this report).

The roll CAS augments the pilot's roll stick inputs and provides roll damping through the aileron, differential stablitor, differential trailing-edge flaps, and differential leading-edge flaps. The center stick position command signal is summed with the roll rate feedback (p) to provide the closed loop control of the ailerons, differential stablitors, differential trailing-edge flaps, and differential leading-edge flaps. Because of the inherent high roll damping of the aircraft at low altitude high speed flight conditions, the roll rate feedback gain is reduced (gain scheduled) in this area. A limited authority roll rate feedback is used to improve trim stability in the area where the CAS roll rate feedback gain is reduced.

The control stick position sensor signal, after it is shaped by a parabolic gradient, provides the desired roll response of the augmented aircraft.

The roll CAS normal mode command path is comprised of an air data scheduled gain (Functions 4, 7, and 13). Function 4 is also the roll rate feedback gain schedule. The gain varies with dynamic and static pressure to provide acceptable loop stability and roll response characteristics throughout the envelope. Notch filters located in the roll rate feedback path attenuate motion sensor inputs due to aeroelastic bending of the aircraft structure. A notch filter is located in the stick position signal to prevent structural mode coupling through the stick position sensor. The frequencies are based on modes determined during Ground Vibration Testing. An additional fourth order roll-off filter is located in the feedback path to provide additional attenuation of the structural mode inputs and high frequency noise, the presence of which was detected during Iron Bird testing.

With wing stores, the roll rate feedback gain is increased for roll rates in excess of 110 degrees per second and the stick command gain (Function 13) is modified in order to limit the maximum roll rate to approximately 150 degrees per second. Without wing stores, the roll rate feedback gain is increased above 190 degrees per second to aid in limiting the maximum roll rate to approximately 220 degrees per second. (Wing stores are not an option in the f18bas simulation).

The maximum roll rate capability with or without stores is limited to 150 degrees per second above 5 g's normal load factor to reduce the vertical tail loads and reduce inertial coupling.
The aileron command gain is scheduled with angle of attack and air data (Functions 35 and 36). The angle-of-attack gain schedule eliminates excessive adverse sideslip during rolling maneuvers for high angles of attack at low dynamic pressure flight conditions. The air data gain schedule reduces the aileron command to zero at high dynamic pressure flight conditions where wing flexibility reverses the effective aileron aerodynamic moments. The air data schedule also avoids hinge moment limits. The aileron command is also limited by an angle of attack and air data schedule (Function 41) to optimize roll coordination.

The roll CAS signal which drives the differential stabilator is multiplied by a gain and then is limited by a gain schedule (Functions 6 and 101) and rate limited at 35 degrees per second to reduce the coupling between the roll and pitch axis at high dynamic pressure where the stabilator approaches hinge moment and bending moment limits. Stabilator bending moment alleviation is provided via a differential stabilator surface command gain scheduled with load factor (Function 101). The differential stabilator command is also limited by the stabilator pitch command (pitch priority) and by an angle-of-attack schedule (Function 41). The aileron and differential stabilator command signals also command rudder (for roll coordination) through the rolling surface-to-rudder interconnect (RSRI). The RSRI is gain scheduled with air data and angle of attack (Functions 30 and 38).

The differential trailing-edge flap command gain is scheduled with air data and angle of attack (Functions 31 and 34). The air data schedule permits the maximum differential deflection available without encountering hinge moment limiting or excessive vertical tail loads. The angle-of-attack schedule reduces the available deflection above 5 degrees AOA and eliminates it above 10 degrees AOA. Differential flaps are not necessary to meet roll performance requirements above these angles of attack.

The differential leading-edge flaps are gain scheduled with air data and load factor (Function 93) to provide improved roll rate in the low to mid altitude transonic speed range. The gain is reduced for increasing load factor, increasing altitude, and decreasing Mach in the transonic speed range.

Differential ailerons are used for active suppression of a wing stores aerelastic oscillation. The forward sensor assembly lateral accelerometer signal is filtered to extract the oscillation component, which then drives the ailerons. The active suppression system is switched on by an air data schedule if the heavy wing stores discrete is set by the Mission Computer.
Figure 9.3. Lateral CAS - (a) Main feedback paths
Figure 9.3. Continued - (b) Aileron and differential stabilator commands
Figure 9.3. Continued - (c) Differential flaps
Figure 9.3. Concluded - (d) Servo command synthesis
### Table 9.3. Lateral (roll) gains in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Function</th>
<th>AFU Mode</th>
<th>Spin Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>RK1</td>
<td>1.117</td>
<td>0.0</td>
</tr>
<tr>
<td>RK2</td>
<td>3.22</td>
<td>6.732</td>
</tr>
<tr>
<td>RK5</td>
<td>F7*(F4*F13)</td>
<td>2.5</td>
</tr>
<tr>
<td>RK6</td>
<td>F4</td>
<td>0.0</td>
</tr>
<tr>
<td>RK10</td>
<td>1.33</td>
<td>0.0</td>
</tr>
<tr>
<td>RK11</td>
<td>1.0</td>
<td>300.0</td>
</tr>
<tr>
<td>RK16</td>
<td>F36</td>
<td>F36</td>
</tr>
<tr>
<td>RK17</td>
<td>F6</td>
<td>F6</td>
</tr>
<tr>
<td>RK18</td>
<td>F31</td>
<td>0.0</td>
</tr>
<tr>
<td>RK22</td>
<td>0.0</td>
<td>0.0</td>
</tr>
<tr>
<td>YK18</td>
<td>See directional axis, Table 9.5</td>
<td></td>
</tr>
</tbody>
</table>

### Table 9.4. Lateral (roll) filters in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Filter</th>
<th>Transfer Function</th>
<th>Where Used</th>
</tr>
</thead>
</table>
| R1     | $\frac{1}{(s/\omega)^2 + 2\zeta(s/\omega) + 1}$ | $\zeta = 0.80$  
$\omega = 90.0$ (r/s) | 2nd order rolloff for roll rate sensor |
| R2     | $\frac{1}{(s/\omega)^2 + 2\zeta_N(s/\omega) + 1}$ | $\zeta_N = 0.05$  
$\zeta_D = 0.50$  
$\omega = 31.0$ (r/s) | 5 Hz notch for stick lateral position sensor |
| R3     | $\frac{1}{(s/\omega)^2 + 2\zeta_N(s/\omega) + 1}$ | $\zeta_N = 0.07$  
$\zeta_D = 0.70$  
$\omega = 44.0$ (r/s) | 7 Hz notch for roll rate sensor |
| R4     | $\frac{1}{(s/\omega)^2 + 2\zeta_N(s/\omega) + 1}$ | $\zeta_N = 0.03$  
$\zeta_D = 0.70$  
$\omega = 107.0$ (r/s) | 17 Hz notch for roll rate sensor |
(a) Roll function 1 - Lateral stick gradient, AFU mode

(b) Roll function 4 - Roll rate feedback gain schedule, AFU mode, \((Q_c, P_s)\)

Figure 9.4 Lateral (roll) CAS Functions.
(c) Roll function 6 - Differential stabilator gain schedule, AFU mode, \((R, P_s)\)

(d) Roll function 7 - Lateral command schedule gain, AFU mode, \((Q_C, P_s)\)

Figure 9.4 Continued.
(e) Roll function 13 - Lateral command schedule gain, AFU mode, \((R_i, P_s)\)

\[
\begin{align*}
A &= (2.6598 \times 10^{-4}) P_{SL} + 0.11501 \quad \text{if } P_{SL} \leq 1470 \\
B &= (-1.2165 \times 10^{-4}) P_{SL} - 0.13018 \quad \text{if } P_{SL} > 1470 \\
A &= (3.4138 \times 10^{-4}) P_{SL} + 0.00417 \\
B &= (-2.1379 \times 10^{-4}) P_{SL} + 0.005713 \\
C &= (4.4840 \times 10^{-5}) P_{SL} + 0.10858
\end{align*}
\]

(f) Roll function 31 - Differential trailing-edge flap gain schedule, AFU mode, \((R_i, P_s)\)

Figure 9.4 Continued.
(g) Roll function 34 - Differential trailing-edge flap gain schedule, AFU mode, ($\alpha$)

(h) Roll function 35 - Lateral forward loop gain schedule, AFU mode, ($\alpha$)

Figure 9.4 Continued.
(i) Roll function 36 - Aileron gain schedule, AFU mode, \((Q_c, P_s, R_i)\)

(j) Roll function 39 - Rudder pedal to roll CAS interconnect gain schedule, AFU mode, \((\alpha)\)

Figure 9.4 Continued.
(k) Roll function 41 - Rolling surface limit schedule, AFU mode, (α, R_i)

(l) Roll function 93A - Differential leading-edge flap gain schedule component, AFU mode, (R_i, P_{S_i})

Figure 9.4 Continued.
(m) Roll function 93B - Differential leading-edge flap gain schedule component, AFU mode, \(P_s\)

(n) Roll function 93C - Differential leading-edge flap gain schedule component, AFU mode, \(N_{Z_{AF}}\)

Figure 9.4 Continued.
(o) Roll function 101 - Differential stabilator load alleviation schedule, AFU mode, \((R_f, P_s, N_{Z\text{AF}})\)

Figure 9.4 Concluded.
Directional Auto Flap Up CAS

Figure 9.5 (a-b) is a simplified version of the diagram "Figure 3 / OFP V10.1" on page 1-99 of MDC report A4107, Vol I, REV. J. Paths having to do with outer loops and the direct electric link (DEL) reversion mode have been deleted. The definition of the directional gains (YKxx) in terms of yaw functions (FUNxx) are given in Table 9.5. Table 9.6 defines the directional filters used in figure 9.5. The yaw functions required to define quantities in both tables 9.1 and 9.2 are defined in figure 9.6 (a-l). The following quote is from pages 1-93, 1-94 of MDC report A4107, Vol I, REV. J. Comments inserted by the authors are in italics. Grammatical hyphens have been added.

Directional control is accomplished by a control-by-wire (CBW) system which commands the twin rudders. The yaw CAS is the primary mode of operation with a DEL (Direct Electric Link) mode from the rudder pedal force transducers to the rudder actuators available for CAS off operation. A rolling surface-to-rudder interconnect (RSRI) is incorporated to minimize the sideslip accompanying roll maneuvers. The block diagram is shown in Figure 3 (Figure 9.5 of this document). Directional functions and logic diagrams are given in Figures 3.1 through 3.27 (Figure 9.6 of this document). Directional digital filters are summarized in Table 1-5 (Table 9.6 of this document).

The normal mode of control is closed loop employing stability axis yaw rate \((r \cos(\alpha) - p \sin(\alpha))\) and lateral acceleration feedback control.

The rudder pedal force transducer signal, after it is shaped by a dead band followed by a parabolic gradient (Function 14), is air data scheduled (Function 10) to prevent a command which would exceed the vertical tail load limits. Air data and angle-of-attack gain schedules (Function 17 and 114) eliminate aircraft departures for full pedal inputs. Full surface authority is available at high angles of attack and low Mach numbers through the rudder pedal-to-rolling surface and rolling surface-to-rudder interconnects described below.

The CAS feedback loop contains a third order roll-off filter to attenuate high frequency noise and structural feedback modes. The computed stability axis yaw rate feedback signal is multiplied by a gain (Function 96) and then shaped by a washout network. The yaw rate (multiplied by cosine of angle of attack) feedback component is used to augment the Dutch roll damping. The remaining signal component, proportional to roll rate multiplied by the sine of angle of attack, is used to help provide sideslip reduction during high angle of attack maneuvering flight. Lateral acceleration feedback aids in reducing sideslip and provides turn coordination. The lateral acceleration feedback signal is shaped by a washout network. The yaw rate feedback gains are air data scheduled (Functions 90 and 96) to increase directional stability at high altitude supersonic speeds and to optimize Dutch roll characteristics at low to mid altitude and speeds, respectively. Additional lateral acceleration air data and angle of attack gain schedules (Functions 112 and 113) improve directional stability above Mach 0.7 and 15 degrees angle of attack. Roll rate multiplied by pitch rate is fed to the directional control system to reduce the effects of inertial coupling (Function 108).

The forward loop consists of a gain scheduled with air data (Function 45). The gain reduces rudder pedal sensitivity in the high dynamic pressure region and optimizes the closed loop directional damping the roll coordination characteristics.

The rolling surface-to-rudder interconnect (RSRI) is used to control rudder deflections to minimize the sideslip accompanying roll maneuvers. The RSRI command is the total commanded differential aileron plus differential stabilator. The RSRI signal is passed through a lead-lag network and multiplied by variable gains, which are functions of angle.

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of attack and air data (Functions 30 and 38). The RSRI allows coordinated rolls to be flown with the feet on the floor.

A rudder pedal-to-rolling surface interconnect is provided to reduce sideslip and angle of attack excursions due to rudder deflection at high angles of attack. The interconnect gain is scheduled with angles of attack and is scheduled to zero at low angles of attack (Function 39).
Figure 9.5. Directional CAS - (a) Main feedback paths
Table 9.5. Directional (yaw) gains in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Function</th>
<th>AFU Mode</th>
<th>Spin Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>YK6</td>
<td>F30</td>
<td>0.0</td>
</tr>
<tr>
<td>YK9</td>
<td>0.00072*F10</td>
<td>0.00144</td>
</tr>
<tr>
<td>YK10</td>
<td>0.234*F10</td>
<td>0.466</td>
</tr>
<tr>
<td>YK13</td>
<td>F90</td>
<td>0.0</td>
</tr>
<tr>
<td>YK17</td>
<td>F96</td>
<td>0.0</td>
</tr>
<tr>
<td>YK18</td>
<td>1.0</td>
<td>0.0</td>
</tr>
<tr>
<td>YK19</td>
<td>F114</td>
<td>0.0</td>
</tr>
<tr>
<td>YK20</td>
<td>F112</td>
<td>0.0</td>
</tr>
<tr>
<td>YK21</td>
<td>F108</td>
<td>0.0</td>
</tr>
</tbody>
</table>

Table 9.6. Directional (yaw) filters in 8.3.3 inner loop CAS

<table>
<thead>
<tr>
<th>Filter</th>
<th>Transfer Function</th>
<th>Where Used</th>
</tr>
</thead>
<tbody>
<tr>
<td>Y1</td>
<td>( \frac{1}{\tau s + 1} )</td>
<td>( \tau = 1/54.6 ) 1st order rolloff in lateral accel. feedback path</td>
</tr>
<tr>
<td>Y2</td>
<td>( \frac{1}{(s/\omega)^2 + 2\zeta(s/\omega) + 1} )</td>
<td>( \zeta = 0.60 ) ( \omega = 37.7 ) (r/s) 2nd order rolloff in lateral accel. feedback path</td>
</tr>
<tr>
<td>Y3</td>
<td>( \frac{s}{\tau s + 1} )</td>
<td>( \tau = 1.0 ) washout used in yaw rate gyro path</td>
</tr>
<tr>
<td>Y5</td>
<td>( \frac{\tau_N s + 1}{\tau_D s + 1} )</td>
<td>( \tau_N = 0.75 ) ( \tau_D = 0.50 ) RSR1 lead-lag</td>
</tr>
<tr>
<td>Y7</td>
<td>( \frac{1}{\tau s + 1} )</td>
<td>( \tau = 1/20.45 ) 1st order rolloff in lateral accel. feedback path</td>
</tr>
</tbody>
</table>
(a) Yaw function 10 - Rudder command gain, AFU mode, \((Q_c)\)

(b) Yaw function 17 - Rudder command gain increment, AFU mode, \((\alpha)\)

Figure 9.6 Directional (yaw) CAS Functions.
(c) Yaw function 30 - RSRI gain schedule, AFU mode, \((Q_c, P_s)\)

(d) Yaw function 38 - RSRI gain schedule, AFU mode, \((\alpha, R_i, P_s)\)

Figure 9.6 Continued.
(e) Yaw function 42 - RSRI nonlinear gradient, AFU mode

(f) Yaw function 45 - Directional forward loop gain schedule, AFU mode, \((Q_c, P_s)\)

Figure 9.6 Continued.
(g) Yaw function 90 - Lateral acceleration feedback gain schedule, AFU mode, \((R_i, P_s)\)

(h) Yaw function 96 - Yaw rate gain schedule, AFU mode, \((Q_c, P_s)\)

Figure 9.6 Continued.
(i) Yaw function 108 - Directional inertial gain schedule, AFU mode, \( (Q_C) \)

(j) Yaw function 112 - Lateral acceleration feedback gain, AFU mode, \( (R_i) \)

Figure 9.6 Continued.
(k) Yaw function 113 - Lateral acceleration feedback gain, AFU mode, ($\alpha$)

(l) Yaw function 114 - Rudder pedal command gain increment, AFU mode, ($R_i$)

Figure 9.6 Concluded.
9.2. Flight Control System Implementation

The f18bas simulation flight control system (FCS) subroutines were created by starting with existing code which modeled flight controls in the Differential Maneuvering Simulator real-time F18 simulation (dmsf18). The code structure and variable nomenclature used in the dmsf18 simulation were left largely unchanged. The interface portions of the control subroutines were modified to be compatible with the Advanced Continuous Simulation Language (ACSL) structure. When calling FORTRAN subroutines from an ACSL simulation, arguments may be passed through a parameter list or through the global ACSL common block, ZZCOM. Using the global common block is risky because all the ACSL defined variables are in ZZCOM and duplicate names can easily exist in the called subroutine. In the interest of execution speed, real-time subroutines use a multiple common block structure to pass arguments instead of parameter lists. The existing real-time common blocks were replaced with parameter lists containing the feedback and driver values required by the FCS subroutines. Sensor and servoactuator models, which appeared in the real-time FCS subroutines, were removed and coded as continuous models in the ACSL main program. Minor modifications were required for the CDC FORTRAN V to VAX FORTRAN conversion. For example, multiple assignment statements can occur on a single line of code in CDC FORTRAN V (A=B=C), but not in VAX FORTRAN. Logical variables pertaining to real-time systems (i.e. the real-time monitor, cockpit lights, strip chart recorders, etc.) were removed. Library functions and subroutines were modified as required for compatibility. Extraneous code which was present for an alternate, expanded, flight control system was removed. A general cleanup of unused variables and dead end code was performed.

Five subroutines comprise the flight control loop. An executive routine, F18FCS, is called from the discrete block, FCS, in the main ACSL routine. The call is scheduled at a regular time interval specified by the ACSL variable, TSFCS. The default interval value is 1/40 (.025) second which represents a compromise between the various sampling rates of 80, 40, 20 and 10 samples per second used by the actual aircraft flight control computer. Sensor signals and pilot control positions are passed to the control routines through the subroutine call parameter list. Surface position commands are then computed and returned to the ACSL main routine through this parameter list. Figure 10.1 presents the overall flow of the executive routine and shows only the main driver and feedback values and the resulting surface deflections. Specific options and special conditions were not shown in this diagram to reduce the clutter. A complete list of passed parameters for subroutine F18FCS is given in tables 9.7 and 9.8.

The executive routine, F18FCS, computes logical variables indicating mode and filter coefficients. The mode logical variables are: spin mode, stores, the supermaneuver switch, automatic speedbrake retraction, and limiter override commands. The filter coefficients are for the dynamic pressure digital filters and the angle of attack signal digital filters. The remaining four control routines are called from F18FCS in the following order:

1. the longitudinal control model, F18LONG,
2. the lateral control model, F18LAT,
3. the directional control model, F18DIR,
4. and an auxiliary routine, F18AUX.

The basic inputs for the longitudinal axis control routine, F18LONG, are:

1. the pilot longitudinal stick command,
2. normal accelerometer feedback,
3. pitch rate gyro feedback,
4. angle-of-attack sensor feedback,
5. dynamic pressure sensor scheduling input,
6. and an aileron to stabilator interconnect command from the lateral control routine.
Figure 9.7. Implementation of the flight control laws
The basic outputs for the longitudinal axis control routine are:
(1) stabilator surface commands,
(2) the leading and trailing-edge flap commands,
(3) and the symmetric thrust vectoring command.

The basic inputs for the lateral axis control routine, F18LAT, are:
(1) the pilot lateral stick command,
(2) roll rate sensor feedback,
(3) normal accelerometers feedback,
(4) lateral accelerometer feedback,
(5) angle of attack sensor feedback,
(6) dynamic pressure sensor scheduling input,
(7) and a rudder to rolling surface crossfeed command from the directional routine.

The basic outputs for the directional axis control routine are:
(1) aileron surface commands,
(2) the interconnect command to the stabilator and flaps,
(3) and a rolling surface to rudder interconnect command.

The basic inputs for the directional axis control routine, F18DIR, are:
(1) the pilot pedal command,
(2) lateral accelerometer feedback,
(3) roll rate gyro feedback,
(4) yaw rate gyro feedback,
(5) angle of attack sensor feedback,
(6) and a rolling surface to rudder interconnect command from the lateral routine.

The basic outputs for the directional axis control routine are:
(1) differential rudder command,
(2) symmetric rudder command,
(3) and a differential thrust vectoring command.

The auxiliary routine blends and schedules the thrust vectoring commands and transforms symmetric and differential surface commands into left and right specific surface commands. The auxiliary routine originally contained servoactuator and hinge moment models. Hinge moments were not being computed at the time of this documentation and the servoactuators existed in the continuous portion of the simulation.

<table>
<thead>
<tr>
<th>f18bas</th>
<th>Local</th>
<th>Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>ALFD</td>
<td>ALPDOT</td>
<td>d/dt of angle of attack, rad/sec</td>
</tr>
<tr>
<td>ALFS</td>
<td>ALFS</td>
<td>angle-of-attack sensor output, degrees</td>
</tr>
<tr>
<td>AYS</td>
<td>NYSENS</td>
<td>lateral accelerometer output, + right, g's</td>
</tr>
<tr>
<td>AZS</td>
<td>NZSENS</td>
<td>vertical accelerometer output, + up, g's</td>
</tr>
<tr>
<td>A81</td>
<td>A81</td>
<td>left engine outlet area, in²</td>
</tr>
<tr>
<td>A82</td>
<td>A82</td>
<td>right engine outlet area, in²</td>
</tr>
<tr>
<td>BETD</td>
<td>BETADOT</td>
<td>d/dt sideslip angle, rad/sec</td>
</tr>
<tr>
<td>BETDG</td>
<td>BETADEG</td>
<td>sideslip angle, degrees</td>
</tr>
<tr>
<td>BLCG</td>
<td>YBASIC</td>
<td>buttock line coordinates of the c.g., inches</td>
</tr>
<tr>
<td>CPL</td>
<td>CPL</td>
<td>left throttle command, degrees</td>
</tr>
<tr>
<td>CPR</td>
<td>CPR</td>
<td>right throttle command, degrees</td>
</tr>
</tbody>
</table>
Table 9.7. Input Parameters for subroutine F18FCS (continued)

<table>
<thead>
<tr>
<th>Name</th>
<th>Local</th>
<th>Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>CSALF</td>
<td>COSALP</td>
<td>cosine of angle of attack</td>
</tr>
<tr>
<td>DAASTR</td>
<td>DELATM</td>
<td>calculated antisymmetric aileron trim deflection, degrees</td>
</tr>
<tr>
<td>DATMBT</td>
<td>DATMBUT</td>
<td>aileron trim button setting, degrees</td>
</tr>
<tr>
<td>DLGPTCT</td>
<td>DLGPTCT</td>
<td>landing gear state, [0,1], 0=gear up, 1=gear down</td>
</tr>
<tr>
<td>DRASTR</td>
<td>DELRTM</td>
<td>calculated antisymmetric rudder trim position, degrees</td>
</tr>
<tr>
<td>DSSY</td>
<td>STBPP</td>
<td>symmetric stabilator deflection, degrees</td>
</tr>
<tr>
<td>DSSYTR</td>
<td>DELSTM</td>
<td>calculated symmetric stabilator trim position, degrees</td>
</tr>
<tr>
<td>DSTMSTB</td>
<td>DSTMBUT</td>
<td>stabilator trim button setting, degrees</td>
</tr>
<tr>
<td>FCRSET</td>
<td>FCRESET</td>
<td>lateral trim reset logical for spin, T/F</td>
</tr>
<tr>
<td>FCSV83</td>
<td>FCSV833</td>
<td>set pitch forward loop gain logical, T/F</td>
</tr>
<tr>
<td>FSCG</td>
<td>XBASIC</td>
<td>fuselage station coordinates of the c.g., inches</td>
</tr>
<tr>
<td>F7BYPS</td>
<td>F7BYPA</td>
<td>schedule lateral gain logical, T/F</td>
</tr>
<tr>
<td>G</td>
<td>G</td>
<td>acceleration due to gravity, ft/sec²</td>
</tr>
<tr>
<td>GLIMTR</td>
<td>GLIMITR</td>
<td>g limit on longitudinal stick logical, T/F</td>
</tr>
<tr>
<td>GLORID</td>
<td>GLORIDE</td>
<td>g limit override logical, T/F</td>
</tr>
<tr>
<td>HSTORE</td>
<td>HSTORE</td>
<td>heavy stores logical, T/F</td>
</tr>
<tr>
<td>ISENS</td>
<td>IDEALS</td>
<td>integer, (0) = ideal sensors, (1) = MDC sensor model</td>
</tr>
<tr>
<td>KFS</td>
<td>KFS</td>
<td>stick spring force constant, n.d.</td>
</tr>
<tr>
<td>LTHVEC</td>
<td>TREVERS</td>
<td>thrust vectoring engaged, T/F</td>
</tr>
<tr>
<td>LTRFLG</td>
<td>TRMMING</td>
<td>logical, true if simulation in trim loop, T/F</td>
</tr>
<tr>
<td>MACH</td>
<td>MACH</td>
<td>Mach number</td>
</tr>
<tr>
<td>MNNSPIN</td>
<td>MANSIN</td>
<td>logical, manual spin mode, T/F</td>
</tr>
<tr>
<td>NTVOPT</td>
<td>NTVOPT</td>
<td>integer, thrust vectoring pitch control blend</td>
</tr>
<tr>
<td>ORIDE</td>
<td>ORIDE</td>
<td>logical, override angle-of-attack limiter, T/F</td>
</tr>
<tr>
<td>PS</td>
<td>PSENS</td>
<td>output of roll rate sensor, °/sec</td>
</tr>
<tr>
<td>PCA</td>
<td>DELTAP</td>
<td>lateral pilot stick input, inches</td>
</tr>
<tr>
<td>PCR</td>
<td>DELTRP</td>
<td>rudder pedal force input, lbs</td>
</tr>
<tr>
<td>PCS</td>
<td>DELTSP</td>
<td>longitudinal pilot stick input, inches</td>
</tr>
<tr>
<td>PCSTR</td>
<td>DLSTPM</td>
<td>calculated trim position for longitudinal stick, in</td>
</tr>
<tr>
<td>PD</td>
<td>PDOT</td>
<td>roll acceleration, rad/sec²</td>
</tr>
<tr>
<td>PSAS</td>
<td>PSAS</td>
<td>logical, pitch stability augmentation system engaged, T/F</td>
</tr>
<tr>
<td>PSTS</td>
<td>PSTATIC</td>
<td>Sensed static pressure, lbs</td>
</tr>
<tr>
<td>QS</td>
<td>QSENS</td>
<td>output of pitch rate sensor, °/sec</td>
</tr>
<tr>
<td>QBAR</td>
<td>QBAR</td>
<td>dynamic pressure, lbs/in²</td>
</tr>
<tr>
<td>QCIS</td>
<td>QCIS</td>
<td>sensed compressible impact pressure, lbs</td>
</tr>
<tr>
<td>QD</td>
<td>QDOT</td>
<td>pitch acceleration, rad/sec²</td>
</tr>
<tr>
<td>RS</td>
<td>RESNS</td>
<td>output of yaw rate sensor, °/sec</td>
</tr>
<tr>
<td>RA2DG</td>
<td>DEGRAD</td>
<td>(180/π)</td>
</tr>
<tr>
<td>RD</td>
<td>RDOT</td>
<td>yaw acceleration, rad/sec²</td>
</tr>
<tr>
<td>RSAS</td>
<td>RSAS</td>
<td>logical, roll stability augmentation system engaged, T/F</td>
</tr>
<tr>
<td>SETVDC</td>
<td>SETTVDC</td>
<td>differential thrust vectoring set, degrees</td>
</tr>
<tr>
<td>SETVSC</td>
<td>SETTVSC</td>
<td>symmetric thrust vectoring set, degrees</td>
</tr>
<tr>
<td>SNALF</td>
<td>SINALP</td>
<td>sine of angle of attack</td>
</tr>
</tbody>
</table>
Table 9.7. Input Parameters for subroutine F18FCS (concluded)

<table>
<thead>
<tr>
<th><strong>fl8bas</strong></th>
<th><strong>Local</strong></th>
<th><strong>Definition</strong></th>
</tr>
</thead>
<tbody>
<tr>
<td>STORES</td>
<td>STORES</td>
<td>logical, stores switch engaged, T/F</td>
</tr>
<tr>
<td>T</td>
<td>T</td>
<td>simulation time, sec</td>
</tr>
<tr>
<td>TSFCS</td>
<td>H</td>
<td>update frame time for flight control subroutines, sec</td>
</tr>
<tr>
<td>TT</td>
<td>TT</td>
<td>total thrust, lbs</td>
</tr>
<tr>
<td>TVDBOT</td>
<td>TVDBOUT</td>
<td>logical, thrust vectoring deadband removed, T/F</td>
</tr>
<tr>
<td>VT</td>
<td>VTOTAL</td>
<td>total airspeed, ft/sec</td>
</tr>
<tr>
<td>WLCG</td>
<td>ZBASIC</td>
<td>waterline coordinate of c.g., inches</td>
</tr>
<tr>
<td>WT</td>
<td>WEIGHT</td>
<td>weight of airplane, lbs</td>
</tr>
<tr>
<td>YSAS</td>
<td>YSAS</td>
<td>logical, yaw stability augmentation system engaged</td>
</tr>
</tbody>
</table>

Table 9.8. Output Parameters for subroutine F18FCS

<table>
<thead>
<tr>
<th><strong>fl8bas</strong></th>
<th><strong>Local</strong></th>
<th><strong>Definition</strong></th>
</tr>
</thead>
<tbody>
<tr>
<td>CAL</td>
<td>DELTACL</td>
<td>left aileron command, degrees</td>
</tr>
<tr>
<td>CAR</td>
<td>DELTACR</td>
<td>right aileron command, degrees</td>
</tr>
<tr>
<td>CFL</td>
<td>DELTFCL</td>
<td>left trailing-edge flap command, degrees</td>
</tr>
<tr>
<td>CFR</td>
<td>DELTFCR</td>
<td>right trailing-edge flap command, degrees</td>
</tr>
<tr>
<td>CNL</td>
<td>DELTNCL</td>
<td>left leading-edge flap command, degrees</td>
</tr>
<tr>
<td>CNR</td>
<td>DELTNCR</td>
<td>right leading-edge flap command, degrees</td>
</tr>
<tr>
<td>CRL</td>
<td>DELTRCL</td>
<td>left rudder command, degrees</td>
</tr>
<tr>
<td>CRR</td>
<td>DELTRCR</td>
<td>right rudder command, degrees</td>
</tr>
<tr>
<td>CSB</td>
<td>DELTSBC</td>
<td>speedbrake command, degrees</td>
</tr>
<tr>
<td>CSL</td>
<td>DELTSCR</td>
<td>left stabilator command, degrees</td>
</tr>
<tr>
<td>CSR</td>
<td>DELTSCR</td>
<td>right stabilator command, degrees</td>
</tr>
<tr>
<td>CTVLL</td>
<td>CTVLL</td>
<td>left lower vane (thrust vectoring) command, degrees</td>
</tr>
<tr>
<td>CTVLU</td>
<td>CTVLL</td>
<td>left upper vane (thrust vectoring) command, degrees</td>
</tr>
<tr>
<td>CTVRL</td>
<td>CTVLL</td>
<td>right lower vane (thrust vectoring) command, degrees</td>
</tr>
<tr>
<td>CTVLR</td>
<td>CTVLL</td>
<td>right upper vane (thrust vectoring) command, degrees</td>
</tr>
<tr>
<td>DLTVCCL</td>
<td>DLTVCCL</td>
<td>left overall vane (thrust vectoring) command, degrees</td>
</tr>
<tr>
<td>DLTVCVR</td>
<td>DLTVCVR</td>
<td>right overall vane (thrust vectoring) command, degrees</td>
</tr>
</tbody>
</table>

The call to the F18 flight control system subroutine (F18FCS) appears twice in the main ACSL program (fl8bas). A flowchart of the main program which illustrates the trimming and main program loops is shown in figures 2.2 through 2.4 in section 2 of this report.

The call to subroutine F18FCS in the initial...end code section of the simulation (figure 2.3) is required by the trimming procedure. F18FCS is only called if the "FCS engaged" logical (LFCS) is true. The call to F18FCS in initial...end code block is required because the ACSL translator sorts the FCS discrete block and places it after the derivative section where it is can then be checked for an event crossing, (T=TFCS in this case). Actuator models represent physical systems (the servoactuator motors that drive the aircraft surfaces) and appear in the continuous
portion of the program code. If the call to F18FCS were not present in the initial section of the ACSL program, the following sequence would occur:

(a) The trim routine would drive a pilot input.
(b) Actuator responses would be computed before the discrete flight control system call.
(c) The surface control command from the previous loop would drive the actuator.
(d) No surface deflection response to the trial pilot input would be computed.
(e) A singularity error would be noted in the trim routine.
(f) 'ESTIMATED [A] MATRIX SINGULAR' would be returned at ACSL prompt.
(g) The simulation would remain untrimmed.

As a result of entering the ACSL runtime command 'START', the simulation process begins execution at the top of the initial section. The top portion of the initial section code is executed once at the beginning of each run (i.e., each time START is entered at the ACSL prompt) and is composed primarily of type declarations (LOGICAL, INTEGER) and constant statements. Constant statements are implemented by the ACSL translator as Fortran DATA statements and the values are entered once into the computer memory when the program is linked. A few direct assignment statements, notably ITFLG=1, also occur in top portion of the initial section code and these values are reset with each run. The continuation statement, 1100..CONTINUE, marks the top of the trim loop. Code appearing after this continuation statement is executed with each loop of the trim sequence until the pass on which the variable ITFLG > 2 is true. Successful trim is indicated by IRFLG=3. The subroutine INITD is called following the !100 statement. This call was included to clear the event list and prevent problems with the crossing value setting of the afterburner switch discrete. Initial values for sensor data are computed prior to the initial flight control system call. The first call to the flight control system computes surface deflection commands based on the initial trim values of pilot control commands. These initial trim pilot control values are read on the first pass through the initial section by the subroutine LOAD from the trim data file 'FI8TR'. The trial pilot control values are used to compute trim are:

(a) longitudinal stick position, PCSTR (Pilot Control Stabilator TRim),
(b) lateral stick position, PCATR, (Pilot Control Aileron TRim),
(c) and pedal force, PCRTR (Pilot Control Rudder TRim)

The logical variable LFCS must be set true for the flight control system to be called. A false value of LFCS will cause the flight control system to be bypassed. The LFCS false condition is present to enable the simulation to be run from direct surface deflection commands. Trim is achieved when the first NXTR elements of the XTRIM array (see table 2.1 in section 2.) are driven to values that cause first NXTR elements of the YTRIM array (table 2.2) to be zero to within some tolerance. The specific combination of XTRIM values used to achieve trim is dependent on which type of trim condition is required (a straight and level trim should not require pedal and lateral stick adjustment, unless some asymmetry was introduced to the aerodynamics). This combination is set up in the trim condition file ('FI8TR'). The procedure for setting up a trim case is more fully described in the section 2.2 of this report.
10. CONCLUSION

A mathematical model and associated computer program (*fl8bas*) to simulate a twin-tailed high performance fighter airplane (McDonnell Douglas F/A-18) were described. The simulation was intended to support advanced control law research for application to high performance aircraft. The modeled flight envelope is extensive, allowing investigations in the high-angle-of-attack portion of the flight regime. While no comparisons with F/A-18 flight data are offered, the simulation is sufficiently detailed to support proof-of-concept studies.

The simulation program was written in the Advanced Continuous Simulation Language (ACSL). Wherever possible, continuous system dynamics were modeled in the DERIVATIVE portion of the ACSL program structure. This policy allows important features of ACSL, such as the automatic generation of linear models and error checking on the numerical integration process, to be utilized. Furthermore, ACSL, by implementing continuous and discrete event dynamics via the DERIVATIVE and DISCRETE block conventions, allows a coherent implementation of multirate digital control laws that should not be lightly discarded.

The simulation math model includes the nonlinear, six degree-of-freedom rigid-body equations, an engine model, sensors, and first-order actuators with rate and position limiting. A simplified form of the F/A-18 digital control laws (version 8.3.3) is implemented, including only the Auto Flap Up (AFU) flight mode used for air combat maneuvering. Aerodynamic forces and moments are calculated from a wind-tunnel-derived database using table look-ups with linear interpolation. The aerodynamic database has an angle-of-attack range of -10° to +90° and a sideslip range of -20° to +20°. The effects of elastic deformation were incorporated in a quasi-static-elastic manner. Elastic degrees of freedom are not actively simulated. In the engine model, the throttle-commanded steady-state thrust level and the dynamic response characteristics of the engine are based on airflow rate as determined from a table look-up. Afterburner dynamics are switched in at a threshold based on the engine airflow and throttle position.

The source code can be obtained from the authors.
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MDC A8575, "F/A-18 Basic Aerodynamic Data", Issue date 31 March 1984, McDonnell Aircraft Company

Roskam, J.; Airplane Flight Dynamics and Automatic Flight Control; Roskam Aviation and Engineering Company; Route 4, Box 274, Ottawa, Kansas; 1979
<table>
<thead>
<tr>
<th>Symbol</th>
<th>Definition</th>
<th>Variable Name</th>
<th>Program Unit</th>
</tr>
</thead>
<tbody>
<tr>
<td>a.r.c.</td>
<td>aerodynamic reference center, in</td>
<td></td>
<td></td>
</tr>
<tr>
<td>b</td>
<td>wing span reference length used for force and moment coefficients, 37.42 ft</td>
<td>BWRF</td>
<td>CSL</td>
</tr>
<tr>
<td>BL\textsubscript{a}</td>
<td>buttock line coordinate of accelerometers, + right, in. (default = 10.5)</td>
<td>NYLOC(2)</td>
<td>CSL</td>
</tr>
<tr>
<td>BL\textsubscript{cg}</td>
<td>buttock line coordinate of c.g., + right, in. (default = 0.0)</td>
<td>FSCG</td>
<td>CSL</td>
</tr>
<tr>
<td>BL\textsubscript{engl}</td>
<td>buttock line coordinate of engine/airframe interface point for left engine, + right, -18.9, in.</td>
<td>BLENGL</td>
<td>CSL</td>
</tr>
<tr>
<td>BL\textsubscript{engR}</td>
<td>buttock line coordinate of engine/airframe interface point for right engine, + right, 18.9, in.</td>
<td>BLENGR</td>
<td>CSL</td>
</tr>
<tr>
<td>BL\textsubscript{rf}</td>
<td>buttock line of aerodynamic reference center, + right, 0.0 in.</td>
<td>BLRF</td>
<td>CSL</td>
</tr>
<tr>
<td>(\bar{c})</td>
<td>wing chord reference length used for force and moment coefficients, 11.52 ft</td>
<td>CWRF</td>
<td>CSL</td>
</tr>
<tr>
<td>(C_{D_0})</td>
<td>basic drag coefficient, controls at zero, rigid airplane, (f(\alpha,M))</td>
<td>CDO</td>
<td>SFAERRF</td>
</tr>
<tr>
<td>(C_{D_{sf}})</td>
<td>total drag coefficient, steady flow, along -x axis in the stability frame, (C_{D</td>
<td>V=0})</td>
<td>CDREFO</td>
</tr>
<tr>
<td>(C_{D\delta_f})</td>
<td>drag coefficient per unit symmetric trailing-edge flap, deg(^{-1}), (f(\alpha,M))</td>
<td>CDDF</td>
<td>SFAERRF</td>
</tr>
<tr>
<td>(C_{D\delta_n})</td>
<td>drag coefficient per unit symmetric leading-edge flap, deg(^{-1}), (f(\alpha,M))</td>
<td>CDDN</td>
<td>SFAERRF</td>
</tr>
<tr>
<td>c.g.</td>
<td>center-of-gravity, in</td>
<td></td>
<td></td>
</tr>
<tr>
<td>(C_{l_0})</td>
<td>basic roll coefficient, controls at zero, rigid airplane, (f(\beta,\alpha,M))</td>
<td>C10</td>
<td>SFAERRF</td>
</tr>
<tr>
<td>(C_{l_p})</td>
<td>roll coefficient per non-dimensional roll rate, (\partial C_l/\partial\left(\frac{pb}{2V}\right))</td>
<td>C1P</td>
<td>SFAERRF</td>
</tr>
</tbody>
</table>

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$C_{lr}$ roll coefficient per non-dimensional yaw rate, $\partial C_l / \partial \left( \frac{\phi}{2V} \right)$, $f(\alpha, M)$

$C_{lsf}$ total roll coefficient, steady flow, about $x$ axis in the body frame, $C_l|_{\psi=0.0}$

$C_{l\Delta\delta_f}$ change in roll coefficient per degree of differential trailing-edge flaps

$C_{l\Delta\delta_H}$ change in roll coefficient per degree differential stabilator

$C_{l\Delta\delta_n}$ change in roll coefficient per degree differential leading-edge flaps

$C_L$ total lift coefficient, along $-z$ axis in the stability frame

$C_{L_0}$ basic lift coefficient, controls at zero, rigid airplane, $f(\alpha, M)$

$C_{Lq}$ lift coefficient per non-dimensional pitch rate, $\partial C_l / \partial \left( \frac{q_e}{2V} \right)$, $f(\alpha, M)$

$C_{Lsf}$ total lift coefficient, steady flow, $= C_L|_{\psi=0.0}$

$C_{L\dot{\alpha}}$ total lift coefficient per non-dimensional rate-of-change in $\alpha$, $\partial C_l / \partial \left( \frac{\dot{\alpha} c}{2V} \right)$, $f(\alpha, M)$

$C_{L\dot{\alpha}_0}$ rigid lift coefficient per non-dimensional rate-of-change in $\alpha$, $\partial C_l / \partial \left( \frac{\dot{\alpha} c}{2V} \right)$ (rigid airplane), $f(\alpha, M)$

$C_{L\delta_f}$ lift coefficient per unit symmetric trailing-edge flap, rigid airplane, deg$^{-1}$, $f(\alpha, M)$

$C_{L\delta_n}$ lift coefficient per unit symmetric leading-edge flap, rigid airplane, deg$^{-1}$, $f(\alpha, M)$
$C_m$  total pitch coefficient, about $y$ axis in the body or stability frame

$C_{m_0}$  basic pitch coefficient, controls at zero, rigid airplane, $f(\alpha, M)$

$C_{m_\alpha}$  pitch coefficient per non-dimensional pitch rate, rigid airplane,

$$\partial C_m / \partial \left( \frac{\dot{\alpha} \dot{\alpha}}{2V} \right) , f(\alpha, M)$$

$C_{m_{sf}}$  total pitch coefficient, steady flow, $= C_m|_{V=0.0}$

$C_{m_{\Delta \alpha}}$  total pitch coefficient per non-dimensional rate-of-change in $\alpha$,

$$\partial C_m / \partial \left( \frac{\dot{\alpha} \dot{\alpha}}{2V} \right) , f(\alpha, M)$$

$C_{m_{\Delta \alpha_0}}$  rigid pitch coefficient per non-dimensional rate-of-change in $\alpha$,

$$\partial C_m / \partial \left( \frac{\dot{\alpha} \dot{\alpha}}{2V} \right) , f(\alpha, M)$$

$C_{m_{\delta f}}$  pitch coefficient per unit symmetric trailing-edge flap, rigid airplane, deg$^{-1}$, $f(\alpha, M)$

$C_{m_{\delta n}}$  pitch coefficient per unit symmetric leading-edge flap, rigid airplane, deg$^{-1}$, $f(\alpha, M)$

$C_{n_0}$  basic yaw coefficient, controls zero, rigid airplane, $f(\beta, \alpha, M)$

$C_{n_p}$  yaw coefficient per non-dimensional yaw rate, $\partial C_n / \partial \left( \frac{\dot{\beta} \dot{\beta}}{2V} \right) , f(\alpha, M)$

$C_{n_r}$  yaw coefficient per non-dimensional yaw rate, $\partial C_n / \partial \left( \frac{\dot{\beta} \dot{\beta}}{2V} \right) , f(\alpha, M)$

$C_{n_{sf}}$  total yaw coefficient, steady flow, about $z$ axis in the body frame, $C_n|_{V=0.0}$

$C_{n_{\Delta \delta f}}$  change in yaw coefficient per degree differential trailing-edge flaps, ($= 0.0$)

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$C_{n\Delta\delta_H}$ change in yaw coefficient per degree differential stabilator, 
\[ f(\alpha, \delta_H, M) \]

$C_{n\Delta\delta_n}$ change in yaw coefficient per degree differential leading-edge flaps, (= 0.0) 

$C_{Y_0}$ basic side force coefficient, controls at zero, rigid airplane, 
\[ f(\beta,\alpha,M) \]

$C_{Y_p}$ side force coefficient per non-dimensional roll rate, 
\[ \partial C_Y/\partial\left(\frac{\rho b}{2V}\right) f(\alpha,M) \]

$C_{Y_f}$ side force coefficient per non-dimensional yaw rate, 
\[ \partial C_Y/\partial\left(\frac{r b}{2V}\right) f(\alpha,M) \]

$C_{Y_{sf}}$ total side force coefficient, steady flow, along y axis in the body or stability frame, $C_T|_{\nu=0.0}$

$C_{Y\Delta\delta_f}$ change in side force coefficient per degree differential trailing-edge flaps, (=0.0)

$C_{Y\Delta\delta_H}$ change in side force coefficient per degree differential stabilator

$C_{Y\Delta\delta_n}$ change in side force coefficient per degree differential leading-edge flaps, (= 0.0)

F force, lbs, eqn. (4.1)

$F_{S_{a}}$ fuselage station coordinate of the accelerometers, + aft, in. (default = 306.75)

$F_{S_{cg}}$ fuselage station coordinate of c.g., + aft, in. (default = 455.0)

$F_{S_{eng}}$ fuselage station coordinate of engine/airframe interface point for right or left engine, + aft, 687.5, in.

$F_{S_{rf}}$ fuselage station of aerodynamic reference center, + aft, 458.56 in.
<table>
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<tr>
<th>Symbol</th>
<th>Definition</th>
<th>Notes</th>
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<tbody>
<tr>
<td>$F_{x_E}$</td>
<td>total x-body component of thrust-induced forces, lbs</td>
<td>FVRE(1)</td>
</tr>
<tr>
<td>$F_{y_E}$</td>
<td>total y-body component of thrust-induced forces, lbs</td>
<td>FVRE(2)</td>
</tr>
<tr>
<td>$F_{z_E}$</td>
<td>total z-body component of thrust-induced forces, lbs</td>
<td>FVRE(3)</td>
</tr>
<tr>
<td>$g$</td>
<td>acceleration due to gravity, 32.174 ft/sec$^2$</td>
<td>G</td>
</tr>
<tr>
<td>$H_p$</td>
<td>altitude appropriate for current density, $\rho$, in the 1962 Standard Atmosphere tables, feet</td>
<td>HRF</td>
</tr>
<tr>
<td>$I_{xx}$</td>
<td>roll moment of inertia, slug-ft$^2$</td>
<td>IXX</td>
</tr>
<tr>
<td>$I_{xz}$</td>
<td>roll-yaw cross coupling moment of inertia, slug-ft$^2$</td>
<td>IXZ</td>
</tr>
<tr>
<td>$I_{yy}$</td>
<td>pitch moment of inertia, slug-ft$^2$</td>
<td>IYY</td>
</tr>
<tr>
<td>$I_{zz}$</td>
<td>yaw moment of inertia, slug-ft$^2$</td>
<td>IZZ</td>
</tr>
<tr>
<td>$l_{xz}$</td>
<td>(1,3) entry of the 3x3 direction cosine matrix $[L]$ that transforms a vector in the local (Earth) frame to the body frame.</td>
<td></td>
</tr>
<tr>
<td>$l_{yz}$</td>
<td>(2,3) entry of the 3x3 direction cosine matrix $[L]$ that transforms a vector in the local (Earth) frame to the body frame.</td>
<td></td>
</tr>
<tr>
<td>$l_{zz}$</td>
<td>(3,3) entry of the 3x3 direction cosine matrix $[L]$ that transforms a vector in the local (Earth) frame to the body frame.</td>
<td></td>
</tr>
<tr>
<td>$m$</td>
<td>mass, slugs, eqn. (4-1)</td>
<td>MASS</td>
</tr>
<tr>
<td>$M$</td>
<td>Mach number</td>
<td></td>
</tr>
<tr>
<td>$p$</td>
<td>+x component of rotational velocity in the body frame, rad/sec</td>
<td>P</td>
</tr>
<tr>
<td>$P_s$</td>
<td>static pressure (lbs/ft$^2$)</td>
<td></td>
</tr>
<tr>
<td>$q$</td>
<td>+y component of rotational velocity in the body frame, rad/sec</td>
<td>Q</td>
</tr>
<tr>
<td>$Q_c$</td>
<td>compressible pressure $1.4<em>P_s</em>M^2/2.0$ (lbs/ft$^2$)</td>
<td></td>
</tr>
<tr>
<td>$r$</td>
<td>+z component of rotational velocity in the body frame, rad/sec</td>
<td>R</td>
</tr>
<tr>
<td>$R_i$</td>
<td>compressible/static pressure $Q_c/P_s$ (lbs/ft$^2$)</td>
<td></td>
</tr>
<tr>
<td>$R_{c_{f}}$</td>
<td>elastic/rigid multiplier on $C_{f}$, (=1.0)</td>
<td>FRC1P</td>
</tr>
</tbody>
</table>

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\( R_{CL\delta A}^F \) elastic/rigid factor applied to aileron roll increment, \( R_{CL\delta A}^{FLT} \)  

\( R_{CL\delta R}^F \) elastic/rigid effectiveness factor applied to roll due to rudder increment, \( f(M,H_p) \)  

\( R_{CL\delta H}^F \) elastic/rigid factor applied to stabilator lift coefficient increment, \( f(M,H_p) \)  

\( R_{CL\delta A}^{FLT} \) flight-derived effectiveness factor applied to aileron lift coefficient increment, \( f(M,H_p) \)  

\( R_{Cm\delta A}^F \) elastic/rigid effectiveness factor applied to aileron pitch coefficient increment, \( f(M,H_p) \)  

\( R_{Cm\delta H}^F \) elastic/rigid factor applied to stabilator pitch coefficient increment, \( f(M,H_p) \)  

\( R_{Cn\delta}^F \) elastic/rigid multiplier on \( C_{np} \), \( f(M,\alpha) \)  

\( R_{Cn\delta A}^F \) elastic/rigid factor applied to aileron yaw coefficient increment, \( f(M,H_p) \)  

\( R_{Cn\delta R}^F \) elastic/rigid effectiveness factor applied to yaw due to rudder increment, \( f(M,H_p) \)  

\( R_{C\gamma p}^F \) elastic/rigid multiplier on \( C_{\gamma p} \), \( f(M,H_p) \)  

\( R_{C\gamma \delta A}^F \) elastic/rigid factor applied to aileron side force coefficient increment, \( f(M,H_p) \)  

\( R_{C\gamma \delta R}^F \) elastic/rigid effectiveness factor applied to side force due to rudder increment, \( f(M,H_p) \)
\( RC_{\delta H} \) effectiveness factor applied to roll due to rudder accounting for stabilator interference, \( f(\alpha, \delta_H) \)

\( RC_{n\delta H} \) effectiveness factor applied to yaw due to rudder accounting for stabilator interference, \( f(\alpha, \delta_H) \)

\( RC_{y\delta H} \) effectiveness factor applied to side force due to rudder accounting for stabilator interference, \( f(\alpha, \delta_H) \)

\( S \) wing reference area used for force and moment coefficients, 400 ft

\( t \) time, seconds

\( TH_L \) total thrust produced by left engine, lbs

\( TH_R \) total thrust produced by right engine, lbs

\( TH_{x;L} \) x-body component of force produced by left engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( TH_{x;R} \) x-body component of force produced by right engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( TH_{y;L} \) y-body component of force produced by left engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( TH_{y;R} \) y-body component of force produced by right engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( TH_{z;L} \) z-body component of force produced by left engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( TH_{z;R} \) z-body component of force produced by right engine at the engine/airframe interface point (687.5,18.9,100.0), lbs

\( u \) +x component of inertial translational velocity in the body frame, ft/sec

\( v \) +y component of inertial translational velocity in the body frame, ft/sec

\( V \) total airspeed, ft/sec

\( w \) +z component of inertial translational velocity in the body frame, ft/sec

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WLₐ \quad \text{waterline coordinate of accelerometers, + up, in.} \quad \text{(default = 91.3)}

WL₉ \quad \text{waterline coordinate of c.g., + up, in. (default = 102.8)}

WL₇ \quad \text{waterline coordinate of engine/airframe interface point for right or left engine, + up, 100.0, in.}

WL₉ \quad \text{waterline coordinate of aerodynamic reference center, + up, 100.0 in.}

xₐrf \quad \text{distance from c.g. to the a.r.c. along X-body axis, + forward,} \quad \text{= } - (FS₉ - FS₉)/12, \text{ ft}

xₐrf \quad \text{distance from c.g. to the engine/airframe interface point along x-body axis, + forward,} \quad \text{= } - (FS₉ - FS₉)/12, \text{ ft}

yₐrf \quad \text{distance from c.g. to the a.r.c. along Y-body axis, + right,} \quad \text{= } (BL₉ - BL₉)/12, \text{ ft}

yₐrf \quad \text{distance from c.g. to the left engine/airframe interface point along y-body axis, + right,} \quad \text{= } (BL₉ - BL₉)/12, \text{ ft}

yₐrf \quad \text{distance from c.g. to the right engine/airframe interface point along y-body axis, + right,} \quad \text{= } (BL₉ - BL₉)/12, \text{ ft}

zₐrf \quad \text{distance from c.g. to the a.r.c. along Z-body axis, + down,} \quad \text{= } - (WL₉ - WL₉)/12, \text{ ft}

zₐrf \quad \text{distance from c.g. to the engine/airframe interface point along z-body axis, + down,} \quad \text{= } -(WL₉ - WL₉)/12, \text{ ft}

\alpha \quad \text{angle of attack, degrees}

\beta \quad \text{sideslip angle, degrees}

\Delta C_{DCL} \quad \text{increment in drag coefficient due to lift, } f(C_{Lsf}, \text{M})

\Delta C_{D\delta_{HL}} \quad \text{increment in drag coefficient due to left stabilator position, rigid airplane, } f(\alpha, \delta_{HL}, \text{M})
<table>
<thead>
<tr>
<th>Increment in Drag Coefficient</th>
<th>Formula</th>
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<tbody>
<tr>
<td>( \Delta C_{D_{s8}} ) due to right stabilator position, rigid airplane, ( f(\alpha, \theta, \delta_R, M) )</td>
<td>( f(\alpha, \theta, \delta_R, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to fully deployed landing gear, ( f(\alpha) )</td>
<td>( f(\alpha) )</td>
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<td>( \Delta C_{D_{s8}} ) due to antisymmetric rudder, ( \Delta C_{D_{s8}} )</td>
<td>( \Delta C_{D_{s8}} )</td>
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<tr>
<td>( \Delta C_{D_{s8}} ) due to symmetric (toe-in) rudder, ( \Delta C_{D_{s8}} )</td>
<td>( \Delta C_{D_{s8}} )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to speed brakes, ( f(\alpha, \delta_R, M) )</td>
<td>( f(\alpha, \delta_R, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to airplane asymmetries, ( f(\alpha) )</td>
<td>( f(\alpha) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to left aileron position, rigid airplane, ( f(\alpha, \delta_L, M) )</td>
<td>( f(\alpha, \delta_L, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to right aileron position, rigid airplane, ( f(\alpha, \delta_R, M) )</td>
<td>( f(\alpha, \delta_R, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to left aileron position, rigid airplane, ( f(\alpha, \delta_L, M) )</td>
<td>( f(\alpha, \delta_L, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to right aileron position, rigid airplane, ( f(\alpha, \delta_R, M) )</td>
<td>( f(\alpha, \delta_R, M) )</td>
</tr>
<tr>
<td>( \Delta C_{D_{s8}} ) due to left aileron position, rigid airplane, ( f(\alpha, \delta_L, M) )</td>
<td>( f(\alpha, \delta_L, M) )</td>
</tr>
</tbody>
</table>
$\Delta C_{L}^{R}$ increment in roll coefficient due to antisymmetric rudder, rigid airplane, used with sign of $\delta_{Ras}$, $f(\alpha, |\delta_{Ras}|, M)$

$\Delta C_{L}^{SB}$ increment to roll coefficient for full $60^\circ$ deflection in speed brakes per degree of sideslip, deg$^{-1}$, $f(\alpha, |\beta|, M)$

$\Delta C_{Lq}^{F}$ increment to basic lift coefficient due to elastic deformation, $f(\alpha, M, H)$

$\Delta C_{L\alpha}^{F}$ elastic increment to $C_{L\alpha}$, $f(\alpha, H)$

$\Delta C_{L\delta_f}^{F}$ increment to $C_{L\delta_f}$ due to elastic deformation, deg$^{-1}$, $f(\alpha, M, H)$

$\Delta C_{L\delta_n}^{F}$ increment to $C_{L\delta_n}$ due to elastic deformation, deg$^{-1}$, $f(\alpha, M, H)$

$\Delta C_{L\delta_{AL}}$ increment in lift coefficient due to left aileron, rigid airplane, $f(\alpha, \delta_{AL}, M)$

$\Delta C_{L\delta_{AR}}$ increment in lift coefficient due to right aileron, rigid airplane, $f(\alpha, \delta_{AL}, M)$

$\Delta C_{L\delta_{HL}}$ increment in lift coefficient due to left stabilator position, rigid airplane, $f(\alpha, \delta_{HL}, M)$

$\Delta C_{L\delta_{HR}}$ increment in lift coefficient due to right stabilator position, rigid airplane, $f(\alpha, \delta_{HR}, M)$

$\Delta C_{L\delta_{LG}}$ increment to lift coefficient for fully deployed landing gear, $f(\alpha)$
\[ \Delta C_{L, \delta_R} \] increment in lift coefficient due to antisymmetric rudder, (=0.0) DCLDR SFAERRF

\[ \Delta C_{L, \delta_{RT}} \] increment in lift coefficient due to symmetric rudder (rudder toe-in), \( f(\alpha, \delta_{RT}, \delta_f/A) \) DCLDRT SFAERRF

\[ \Delta C_{L, \delta_{SB}} \] increment to lift coefficient for full 60 degree deflection in speed brakes, \( f(\alpha, M) \) DCLSB SFAERRF

\[ \Delta C_{m_0}^F \] increment to basic pitch coefficient due to elastic deformation, \( f(\alpha, M, H_p) \) DCMOF SFAERRF

\[ \Delta C_{m_q}^F \] increment to \( C_{m_q} \) due to elastic deformation DCMQF SFAERRF

\[ \Delta C_{m_\delta_x}^F \] elastic increment to \( C_{m_\delta_x} \), \( f(\alpha, H) \) DCMADF USAERRF

\[ \Delta C_{m_\delta_f}^F \] increment to \( C_{m_\delta_f} \) due to elastic deformation, \( \text{deg}^{-1} \) \( f(\alpha, M, H_p) \) DCMDDF SFAERRF

\[ \Delta C_{m_\delta_n}^F \] increment to \( C_{m_\delta_n} \) due to elastic deformation, \( \text{deg}^{-1} \) \( f(\alpha, M, H_p) \) DCMDF SFAERRF

\[ \Delta C_{m_{LEX}} \] increment in pitch due to the leading-edge wing extensions, \( f(\alpha, M) \) DCMLEX SFAERRF

\[ \Delta C_{m_{A_L}} \] increment in pitch coefficient due to left aileron, rigid airplane, \( \text{deg}^{-1}, f(\alpha, \delta_{A_L}, M) \) DCMDAL SFAERRF

\[ \Delta C_{m_{A_R}} \] increment in pitch coefficient due to right aileron, rigid airplane, \( \text{deg}^{-1}, f(\alpha, \delta_{A_R}, M) \) DCM DAR SFAERRF

\[ \Delta C_{m_{H_L}} \] increment in pitch coefficient due to left stabilator position, rigid airplane, \( f(\alpha, \delta_{H_L}, M) \) DCMDH SFAERRF
\( \Delta C_{m_{\delta_H}} \) increment in pitch coefficient due to right stabilator position, rigid airplane, \( f(\alpha, \delta_{HR}, M) \)  
\( \Delta C_{m_{\delta_L}} \) increment to pitch coefficient for fully deployed landing gear, \( f(\alpha) \)  
\( \Delta C_{m_{\delta_R}} \) increment in pitch coefficient due to antisymmetric rudder, \( f(\alpha, |\delta_R|, M) \)  
\( \Delta C_{m_{\delta_{RT}}} \) increment in pitch coefficient due to symmetric rudder (rudder toe-in), \( f(\alpha, \delta_{RT}, \delta_{f/A}) \)  
\( \Delta C_{m_{\delta_S}} \) increment to pitch coefficient for full 60 degree deflection in speed brakes, \( f(\alpha, M) \)  
\( \Delta C_{n_r} \) increment to \( C_{n_r} \) due to elastic deformation, \( f(M, H_p) \)  
\( \Delta C_{n_\beta} \) increment to \( C_{n_\beta} \) due to elastic deformation, \( f(M, H_p) \)  
\( \Delta C_{n_{\delta_A}} \) increment in yaw coefficient due to left aileron position, rigid airplane, \( f(\alpha, \delta_{AL}, M) \)  
\( \Delta C_{n_{\delta_R}} \) increment in yaw coefficient due to right aileron position, rigid airplane, \( f(\alpha, \delta_{AR}, M) \)  
\( \Delta C_{n_\delta_f} \) increment in yaw coefficient for full 20 degree deployment of symmetric trailing-edge flaps, rigid airplane, used with sign of \( \beta \), \( f(|\beta|, \alpha, M) \)  
\( \Delta C_{n_\delta_n} \) increment in yaw coefficient for full 25 degree deployment of symmetric leading-edge flaps, rigid airplane, used with sign of \( \beta \), \( f(|\beta|, \alpha, M) \)  

DCMDHR SFAERRF  
DCMDLG SFAERRF  
DCMDR SFAERRF  
DCMDRT SFAERRF  
DCMSB SFAERRF  
DCNRF SFAERRF  
DCNBF SFAERRF  
DCNDAL SFAERRF  
DCNDAR SFAERRF  
DCNDF SFAERRF  
DCNDN SFAERRF
\( \Delta C_{n \delta_R} \) \  increment in yaw coefficient due to antisymmetric rudder, rigid airplane, used with sign of \( \delta_{Ras} \), \( f(\alpha, |\delta_{Ras}|, M) \)

\( \Delta C_{n \delta_{SB}} \) \  increment to yaw coefficient for full 60 degree deflection in speed brakes per degree of sideslip, \( \deg^{-1} \), \( f(\alpha, |\beta|, M) \)

\( \Delta C_Y^F \) \  increment to \( C_Y \) due to elastic deformation, \( f(M, \rho) \)

\( \Delta C_Y^F \) \  increment to \( C_Y \) due to elastic deformation, \( f(M, \rho) \)

\( \Delta C_Y^F \) \  increment to \( C_Y \) due to elastic deformation, \( f(M, \rho) \)

\( \Delta C_Y^\delta_{AL} \) \  increment in side force coefficient due to left aileron position, rigid airplane, \( f(\alpha, \delta_{AL}, M) \)

\( \Delta C_Y^\delta_{AR} \) \  increment in side force coefficient due to right aileron position, rigid airplane, \( f(\alpha, \delta_{AR}, M) \)

\( \Delta C_Y^\delta_f \) \  increment in side force coefficient for full 20 degree deployment of symmetric trailing-edge flaps, rigid airplane, used with sign of \( \beta \), \( f(|\beta|, \alpha, M) \)

\( \Delta C_Y^\delta_n \) \  increment in side force coefficient for full 25 degree deployment of symmetric leading-edge flaps, rigid airplane, used with sign of \( \beta \), \( f(|\beta|, \alpha, M) \)

\( \Delta C_Y^\delta_R \) \  increment in side force coefficient due to antisymmetric rudder, rigid airplane, used with sign of \( \delta_{Ras} \), \( f(\alpha, |\delta_{Ras}|, M) \)

\( \Delta C_Y^\delta_{SB} \) \  increment to side force coefficient for full 60 degree deflection in speed brakes per degree of sideslip, \( \deg^{-1} \), \( f(\alpha, |\beta|, M) \)

\( \theta \) \  pitch angle, radians

\( \rho \) \  density of the air, slugs/ft\(^3\)

\( \phi \) \  roll angle, radians
$\Psi$ yaw angle, radians

$\Psi_{\text{engL}}$ left engine cant angle in x-y plane, pos nose right, ($-1.98^\circ$)

$\Psi_{\text{engR}}$ right engine cant angle in x-y plane, pos nose right, ($1.98^\circ$)

**Subscripts**

- $a$: aerodynamic, with respect to the air mass
- $A$: due to air loads
- $\text{asm}$: due to asymmetries
- $E,\text{eng}$: engine induced
- $G$: due to gravity
- $\text{rf}$: quantity computed at the aerodynamic reference center (a.r.c.)
- $\text{wg}$: component due to winds, turbulence, or gust
- $x$: component along the $X_B$ (body frame) axis
- $y$: component along the $Y_B$ (body frame) axis
- $z$: component along the $Z_B$ (body frame) axis

**Notation**

- $\{ \}$ column vector
- $[ \ ]$ matrix or row vector
- $[ \ ]'$ transpose of $[ \ ]$

$x_{l_b}^{r_a}$ the variable $x$ restricted to the range, $b \leq x \leq a$, typically used to describe a function argument that is limited.

**Acronyms**

- ACSL: Advanced Continuous Simulation Language
- AFU: Auto-Flap Up mode of the F/A-18 Flight Control System (8.3.3 PROM)
- AGCB: Aircraft Guidance and Controls Branch at NASA LaRC
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<tr>
<th>Abbreviation</th>
<th>Description</th>
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<tbody>
<tr>
<td>BL</td>
<td>Buttock line coordinate, + right</td>
</tr>
<tr>
<td>CAS</td>
<td>Control Augmentation System</td>
</tr>
<tr>
<td>CDC</td>
<td>Control Data Corporation</td>
</tr>
<tr>
<td>DMS</td>
<td>Differential Maneuvering Simulator twin-dome facility at NASA LaRC</td>
</tr>
<tr>
<td>dmsf18</td>
<td>Real-time simulation program of an F/A-18 developed at LaRC for use in the DMS facility.</td>
</tr>
<tr>
<td>FIT</td>
<td>Functional Integration Technology</td>
</tr>
<tr>
<td>FS</td>
<td>Fuselage station coordinate, + aft</td>
</tr>
<tr>
<td>f18bas</td>
<td>Simulation model and computer program described in this document</td>
</tr>
<tr>
<td>f18harv</td>
<td>Simulation model and computer program resulting from extensive modifications to the f18bas program and in support of the HARV research program</td>
</tr>
<tr>
<td>HARV</td>
<td>High-Angle-of-Attack Research Vehicle</td>
</tr>
<tr>
<td>LaRC</td>
<td>Langley Research Center</td>
</tr>
<tr>
<td>LEX</td>
<td>Leading Edge Extension</td>
</tr>
<tr>
<td>MDC</td>
<td>McDonnel Douglas Corporation</td>
</tr>
<tr>
<td>mdcf18</td>
<td>Batch simulation program of an F/A-18 developed by MDC and obtained for use at LaRC around 1986.</td>
</tr>
<tr>
<td>PROM</td>
<td>Programmable Read Only Memory</td>
</tr>
<tr>
<td>PSF</td>
<td>pounds per square foot</td>
</tr>
<tr>
<td>RSRI</td>
<td>Roll surface to rudder interconnect</td>
</tr>
<tr>
<td>SPIN</td>
<td>Spin mode of AFU in F-18 8.3.3 PROM set</td>
</tr>
<tr>
<td>STORES</td>
<td>Logical for wing stores on or off (Always off)</td>
</tr>
<tr>
<td>WL</td>
<td>Waterline coordinate, + up</td>
</tr>
</tbody>
</table>
APPENDIX A - SIMULATION VARIABLES

Simulation Variable Naming Plan

Development of the simulation model involved the efforts of several engineers and programmers and has included receipt of data, documentation, and several Fortran subroutines from MDC and other sources. This effort has given the authors a keen sense of the desirability of a "standard" variable nomenclature for coding simulation models. Without a "standard" variable nomenclature, it was generally impossible to follow the coded logic without having the documentation in hand. This section describes our efforts at maintaining a consistent variable naming strategy. The creation of meaningful variable names was made challenging by the restriction in ACSL version 9 to six character variable names. ACSL version 10 supports longer variable names.

The authors developed a system for naming variables. This should not be confused with issuing a variable dictionary for project personnel to use. The philosophy behind the variable nomenclature system was that any given variable name could be constructed from a set of predefined mnemonics (base names; prefix and suffix modifiers), given an appropriate set of construction rules. This philosophy is based upon ideas enunciated by Mitchell and documented in Arbuckle (1987). A set of mnemonics developed by the authors is listed in tables A.1 through A.3. The construction rules for creating a variable name are as follows:

1) In keeping with the ANSI Fortran 77 standard and the requirements of ACSL, all variable names are six characters or less.
2) Prefix and suffix modifiers may only be used in combination with a base name.
3) Multiple prefixes may only be used if their nesting levels are different. The highest nesting level prefix will be leftmost, followed by the base name.
4) Multiple suffixes may only be used if their nesting levels are different. The highest nesting level suffix will be rightmost.
5) Base name truncation may be used to meet the requirement that all names be six characters or less. If truncation is required, remove the right character of the base name.

As an example of using the nomenclature system and construction rules, consider a variable defining $\beta$ in units of degrees at the aerodynamic reference point. The base name for $\beta$ is BET, the suffixes are DG and RF, respectively. The suffix DG has a nesting level of two, and the suffix RF has a nesting level of three (see table A.3). Constructing the variable name using rule number five results in BETDGRF, which is a seven-character name and violates rule number one. Using rule number six, remove the right character of BET to give us BEDGRF as the variable name which satisfies the construction rules.

When simulation model components were derived from preexisting code, the authors were reluctant to totally discard the variable name structure already in place. Not all of the variable names in the simulation were constructed according to the rules of this section.
### Table A.1 Base Variable Naming Plan

<table>
<thead>
<tr>
<th>Base Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ALF</td>
<td>angle of attack, $\alpha$, radians</td>
</tr>
<tr>
<td>BET</td>
<td>sideslip angle, $\beta$, radians</td>
</tr>
<tr>
<td>C</td>
<td>control surface command, degrees</td>
</tr>
<tr>
<td>Cxx</td>
<td>direction cosine, $xx = {XX, XY, XZ, YX, ..., ZY, ZZ}$</td>
</tr>
<tr>
<td>D</td>
<td>control surface deflection, degrees</td>
</tr>
<tr>
<td>DG2RD</td>
<td>degrees to radians conversion factor ($\pi/180$), $\text{rad}^\circ$</td>
</tr>
<tr>
<td>En</td>
<td>quaternion, $n = 0,1,2,3$</td>
</tr>
<tr>
<td>GAM</td>
<td>longitudinal flight path angle, radians</td>
</tr>
<tr>
<td>H</td>
<td>$z$ component of position in Earth frame (altitude above mean sea level), ft</td>
</tr>
<tr>
<td>L</td>
<td>logical or integer switch</td>
</tr>
<tr>
<td>MACH</td>
<td>Mach number</td>
</tr>
<tr>
<td>P</td>
<td>$x$ body component of rotational velocity, rad/sec</td>
</tr>
<tr>
<td>PHI</td>
<td>Euler bank angle, $\psi$, radians</td>
</tr>
<tr>
<td>PSI</td>
<td>Euler yaw angle, $\phi$, radians</td>
</tr>
<tr>
<td>Q</td>
<td>$y$ body component of rotational velocity, rad/sec</td>
</tr>
<tr>
<td>QBAR</td>
<td>dynamic pressure, $\dot{q}$, lb/ft$^2$</td>
</tr>
<tr>
<td>R</td>
<td>$z$ body component of rotational velocity, rad/sec</td>
</tr>
<tr>
<td>RD2DG</td>
<td>radians to degrees ($180/\pi$), $^\circ$/rad</td>
</tr>
<tr>
<td>RHO</td>
<td>air density, slugs/ft$^3$</td>
</tr>
<tr>
<td>TH</td>
<td>total thrust, lb</td>
</tr>
<tr>
<td>THE</td>
<td>Euler pitch angle, $\theta$, radians</td>
</tr>
<tr>
<td>U</td>
<td>$x$ body frame component of translational velocity, ft/sec</td>
</tr>
<tr>
<td>V</td>
<td>$y$ body frame component of translational velocity, ft/sec</td>
</tr>
<tr>
<td>VT</td>
<td>total velocity magnitude (inertial), ft/sec</td>
</tr>
<tr>
<td>W</td>
<td>$z$ body frame component of translational velocity, ft/sec</td>
</tr>
<tr>
<td>X</td>
<td>$x$ component of position in earth frame, ft</td>
</tr>
<tr>
<td>Y</td>
<td>$y$ component of position in earth frame, ft</td>
</tr>
</tbody>
</table>

### Table A.2 Prefix Naming Plan

<table>
<thead>
<tr>
<th>Base Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CS</td>
<td>trigonometric cosine of $x$</td>
</tr>
<tr>
<td>R</td>
<td>ratio</td>
</tr>
<tr>
<td>SN</td>
<td>trigonometric sine of $x$</td>
</tr>
</tbody>
</table>
Table A.3  Suffix Naming Plan

<table>
<thead>
<tr>
<th>Suffix</th>
<th>Level</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>intermediate value of a state</td>
</tr>
<tr>
<td>2</td>
<td>2</td>
<td>quantity has been squared</td>
</tr>
<tr>
<td>A</td>
<td>1</td>
<td>applies to aileron</td>
</tr>
<tr>
<td>A</td>
<td>2</td>
<td>aerodynamic</td>
</tr>
<tr>
<td>B</td>
<td>2</td>
<td>bias</td>
</tr>
<tr>
<td>CG</td>
<td>2</td>
<td>airplane center-of-gravity</td>
</tr>
<tr>
<td>D</td>
<td>1</td>
<td>d/dt, time rate of change</td>
</tr>
<tr>
<td>E</td>
<td>2</td>
<td>engine, thrust related</td>
</tr>
<tr>
<td>F</td>
<td>1</td>
<td>applies to trailing-edge flaps</td>
</tr>
<tr>
<td>I</td>
<td>2</td>
<td>inertial</td>
</tr>
<tr>
<td>IC</td>
<td>5</td>
<td>initial condition, variable is in the state variable</td>
</tr>
<tr>
<td></td>
<td></td>
<td>i.c. array</td>
</tr>
<tr>
<td>L</td>
<td>4</td>
<td>lift</td>
</tr>
<tr>
<td>LL</td>
<td>2</td>
<td>lower limit</td>
</tr>
<tr>
<td>LM</td>
<td>2</td>
<td>limit</td>
</tr>
<tr>
<td>LN</td>
<td>5</td>
<td>dummy variable used only to act as a possible input</td>
</tr>
<tr>
<td></td>
<td></td>
<td>for ACSL ANALYZ functions</td>
</tr>
<tr>
<td>MN</td>
<td>2</td>
<td>minimum</td>
</tr>
<tr>
<td>MX</td>
<td>2</td>
<td>maximum</td>
</tr>
<tr>
<td>P</td>
<td>2</td>
<td>probe</td>
</tr>
<tr>
<td>PLA</td>
<td>1</td>
<td>power lever angle</td>
</tr>
<tr>
<td>R</td>
<td>2</td>
<td>rudder</td>
</tr>
<tr>
<td>R</td>
<td>4</td>
<td>right</td>
</tr>
<tr>
<td>RA</td>
<td>2</td>
<td>variable has units of radians or rad/sec</td>
</tr>
<tr>
<td>RF</td>
<td>3</td>
<td>reference quantity</td>
</tr>
<tr>
<td>S</td>
<td>1</td>
<td>stabilator</td>
</tr>
<tr>
<td>S</td>
<td>2</td>
<td>sensor</td>
</tr>
<tr>
<td>SB</td>
<td>1</td>
<td>speed brake</td>
</tr>
<tr>
<td>SG</td>
<td>4</td>
<td>signal</td>
</tr>
<tr>
<td>SL</td>
<td>2</td>
<td>sea level</td>
</tr>
<tr>
<td>SY</td>
<td>3</td>
<td>symmetric</td>
</tr>
<tr>
<td>TR</td>
<td>5</td>
<td>value calculated for trim, may not be a state variable</td>
</tr>
<tr>
<td>UL</td>
<td>2</td>
<td>upper limit</td>
</tr>
<tr>
<td>WG</td>
<td>2</td>
<td>aerodynamic disturbance, wind or gust</td>
</tr>
<tr>
<td>X</td>
<td>2</td>
<td>x body frame component</td>
</tr>
<tr>
<td>Y</td>
<td>2</td>
<td>y body frame component</td>
</tr>
<tr>
<td>Z</td>
<td>2</td>
<td>z body frame component</td>
</tr>
<tr>
<td>ZR</td>
<td>2</td>
<td>&quot;zero&quot;, reference to an i.c. or trim state</td>
</tr>
</tbody>
</table>

Simulation Dictionary Option

ACSL provides for maintaining a simulation dictionary. If the logical LVDEF in the simulation is set true at run time, a call to LISTD(29) is made in the terminal block of the translator source code. Calling LISTD(29) causes a list of variable names and definitions to be read from unit 29 and written to the "PRN" output unit along with the values of all the variables in the simulation [ACSL (1987)]. All variables and their values are listed on the "PRN" output unit. The variables not found on the dictionary (unit 29) are simply listed without definitions. The ACSL executive program is not aware of any variables internal to called Fortran subroutines.
List of Simulation Variables

A81  left engine nozzle exit area, in^2
A82  right engine nozzle exit area, in^2
ABL  marker for left afterburner "state update" discrete block
ABLRR  left engine afterburner thrust lower rate limit, lbs/sec
ABLRL  right engine afterburner thrust lower rate limit, lbs/sec
ABR  marker for right afterburner "state-update" discrete block
ABSWL  true. if left engine afterburner is activated
ABSWR  true. if right engine afterburner is activated
ABULL  left engine afterburner thrust upper rate limit, lbs/sec
ABULR  right engine afterburner thrust upper rate limit, lbs/sec
ALDGRF  angle of attack at the aerodynamic reference center (a.r.c.), degrees
ALF  angle of attack at the c.g., radians
ALFB  air data probe local angle-of-attack bias
ALFD  d/dt of ALF, rad/sec
ALFDG  angle of attack at the c.g., degrees
ALFP  d/dt of ALFP, degree/sec
ALFLM  limited angle of attack, used in Pitot tube sensor model, degrees
ALFR  air data probe angle of attack, degrees
ALFPIC  air data probe angle-of-attack initial condition, degrees
ALFS  sensed angle of attack, equal to ALFS0 or ALFS1 based ISENS = 0 or 1
ALFS0  actual or true angle of attack, equal to ALFDG, degrees
ALFS1  output of air data models, degrees
ALFTR  angle of attack required for trim, radians
AX  acceleration in x-body direction, g's
AY  acceleration in y-body direction, g's
AYS  sensed lateral acceleration, AY, equal to AYS0 or AYS1 based on ISENS = 0 or 1, g's
AYS0  true lateral acceleration, = AY, g's
AYS1  output of lateral accelerometer sensor model, g's
AYW  wind axis lateral acceleration, ft/sec^2
AZ  acceleration in z-body direction, g's
AZEL  azimuth angle of left engine as installed, 1.98 degrees
AZER  azimuth angle of right engine as installed, 1.98 degrees
AZS  sensed normal acceleration, equal to AZS0 or AZS1 based on ISENS, g's
AZS0  true normal acceleration, equal to AZ, g's
AZS1  output of normal accelerometer sensor model, g's
AZW  wind axis normal acceleration, ft/sec^2
BEDGRF  sideslip angle at the aerodynamic reference center (a.r.c.), degrees
BET  sideslip angle at the c.g., radians
BETD  d/dt of BET, rad/sec
BETDG  sideslip angle at the c.g., degrees
BETTR  value of BET required for trim, calculated in trim search, radians
BLCG  buttock line coordinate of the center of gravity, inches
BLENGL  buttock line coordinate of the engine/airframe interface, left engine, -18.9 in.
BLENGR  buttock line coordinate of the engine/airframe interface, right engine, 18.9 in.
BLRF  buttock line coordinate of the aerodynamic reference center, 0.00 inches
BWRF  reference wing span used for nondimensional aero coefficients, 37.42 ft
C1RFSE  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFSG  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFSS  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFST  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFSE  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFSG  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFSS  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
C1RFST  total steady-flow span used for nondimensional aero coefficients, 37.42 ft
CAASLN  commanded antisymmetric aileron, linearization input only, degrees
CAASLP  commanded left aileron, degrees
CAASSP  commanded right aileron, degrees
commanded antisymmetric aileron, linearization input only, degrees

dynamic check perturbation signal to symmetric aileron command, degrees

left power lever angle command from auto throttle, degrees

right power lever angle command from auto throttle, degrees

drag coefficient at aerodynamic reference center, steady flow (\( \alpha = 0 \)) , n.d.

commanded antisymmetric trailing-edge flap, linearization input only, degrees

dynamic check perturbation signal to antisymmetric trailing-edge flap command, degrees

command to left trailing-edge flap actuator, degrees

command to right trailing-edge flap actuator, degrees

commanded symmetric trailing-edge flap, linearization input only, degrees

dynamic check perturbation signal to symmetric trailing-edge flap command, degrees

simulation communication interval, time interval at which data is written to the
master time history file or available at the screen, seconds

lift coefficient at aerodynamic reference center, steady flow (\( \alpha = 0 \)), n.d.

Target trim value for CLRFSF if "12" is in active part of IYSEL array.

pitch (about y-body axis) coefficient at aerodynamic reference point, steady flow

\( \alpha = 0 \)), n.d.

commanded antisymmetric leading-edge flap, linearization input only, degrees

dynamic check perturbation signal to antisymmetric leading-edge flap command, degrees

command to left leading-edge flap actuator, degrees

command to right leading-edge flap actuator, degrees

yaw (about z-body axis) coefficient at aerodynamic reference point, steady flow

\( \alpha = 0 \)), n.d.

commanded symmetric leading-edge flap, linearization input only, degrees

dynamic check perturbation signal to symmetric leading-edge flap command, degrees

intermediate quantity, \( \frac{c}{2V} \), sec

commanded antisymmetric power lever angle, linearization input only, degrees

dynamic check perturbation signal to antisymmetric power lever angle command, degrees

left power lever angle command from the pilot, degrees

left power lever angle command from the pilot required to for trim, degrees

right power lever angle command from the pilot, degrees

right power lever angle command from the pilot required to for trim, degrees

commanded symmetric power lever angle, linearization input only, degrees

dynamic check perturbation signal to symmetric power lever angle command, degrees

commanded symmetric power lever angle, signal array used in IDYNCK=3 option
wherein an arbitrary input stream can be constructed

commanded antisymmetric rudder (both t.e.left), linearization input only, degrees

dynamic check perturbation signal to antisymmetric rudder, degrees

command to left rudder actuator, degrees

command to right rudder actuator, degrees

commanded symmetric rudder, linearization input only, degrees

dynamic check perturbation signal to symmetric rudder command, degrees

cosine of angle of attack at the c.g., \( \cos(\alpha) \)
<table>
<thead>
<tr>
<th>Variable</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CSALRF</td>
<td>cosine of angle of attack at the a.r.c., ( \cos(\alpha_{\text{ref}}) )</td>
</tr>
<tr>
<td>CSASLN</td>
<td>commanded antisymmetric stabilator, linearization input only, degrees</td>
</tr>
<tr>
<td>CSASP</td>
<td>dynamic check antisymmetric stabilator command, degrees</td>
</tr>
<tr>
<td>CSAZEL</td>
<td>cosine of azimuth angle of left engine as installed, ( \cos(AZEL) )</td>
</tr>
<tr>
<td>CSAZER</td>
<td>cosine of azimuth angle of right engine as installed, ( \cos(AZER) )</td>
</tr>
<tr>
<td>CSB</td>
<td>command to speed brake actuator, degrees</td>
</tr>
<tr>
<td>CSBET</td>
<td>cosine of sideslip angle at the c.g.</td>
</tr>
<tr>
<td>CSL</td>
<td>command to left stabilator actuator, degrees</td>
</tr>
<tr>
<td>CSPHI</td>
<td>cosine of the roll angle PHI</td>
</tr>
<tr>
<td>CSPHO2</td>
<td>( \cos(\Phi/2) )</td>
</tr>
<tr>
<td>CSPSO2</td>
<td>( \cos(PSI/2) )</td>
</tr>
<tr>
<td>CSR</td>
<td>command to right stabilator actuator, degrees</td>
</tr>
<tr>
<td>CSSYN</td>
<td>commanded symmetric stabilator, linearization input only, degrees</td>
</tr>
<tr>
<td>CSSYP</td>
<td>dynamic check perturbation signal to symmetric stabilator command, degrees</td>
</tr>
<tr>
<td>CSTHE</td>
<td>cosine of the pitch angle, ( \cos(\theta) )</td>
</tr>
<tr>
<td>CSTHIV</td>
<td>( 1. / \text{CSTHLM} )</td>
</tr>
<tr>
<td>CSTHLM</td>
<td>( \cos(\theta) ) if (</td>
</tr>
<tr>
<td>CSTHO2</td>
<td>( \cos(\Theta/2) )</td>
</tr>
<tr>
<td>CSTVLA</td>
<td>cosine of the thrust vectoring vane orientation angle</td>
</tr>
<tr>
<td>CTLL</td>
<td>lower left thrust vector vane deflection command, degrees</td>
</tr>
<tr>
<td>CTLU</td>
<td>upper left thrust vector vane deflection command, degrees</td>
</tr>
<tr>
<td>CTURL</td>
<td>lower right thrust vector vane deflection command, degrees</td>
</tr>
<tr>
<td>CTVRU</td>
<td>upper right thrust vector vane deflection command, degrees</td>
</tr>
<tr>
<td>CWRF</td>
<td>aerodynamic wing reference chord, ( c ), 11.52 ft</td>
</tr>
<tr>
<td>CXRFSF</td>
<td>aerodynamic axial force (x-body) coefficient at a.r.p., steady flow (( \alpha = 0 )), n.d.</td>
</tr>
<tr>
<td>CXX</td>
<td>direction cosine, x body component of unit x Earth frame vector</td>
</tr>
<tr>
<td>CXY</td>
<td>direction cosine, x body component of unit y Earth frame vector</td>
</tr>
<tr>
<td>CXZ</td>
<td>direction cosine, x body component of unit z Earth frame vector</td>
</tr>
<tr>
<td>CYRFSF</td>
<td>aerodynamic side force (y-body) coefficient at a.r.p., steady flow (( \alpha = 0 )), n.d.</td>
</tr>
<tr>
<td>CYX</td>
<td>direction cosine, y body component of unit x Earth frame vector</td>
</tr>
<tr>
<td>CYY</td>
<td>direction cosine, y body component of unit y Earth frame vector</td>
</tr>
<tr>
<td>CYZ</td>
<td>direction cosine, y body component of unit z Earth frame vector</td>
</tr>
<tr>
<td>CZRFSF</td>
<td>aerodynamic normal force (z-body) coefficient at a.r.p., steady flow (( \alpha = 0 )), n.d.</td>
</tr>
<tr>
<td>CZX</td>
<td>direction cosine, z body component of unit x Earth frame vector</td>
</tr>
<tr>
<td>CZY</td>
<td>direction cosine, z body component of unit y Earth frame vector</td>
</tr>
<tr>
<td>CZZ</td>
<td>direction cosine, z body component of unit z Earth frame vector</td>
</tr>
<tr>
<td>DA0L</td>
<td>position output of left aileron actuator, degrees</td>
</tr>
<tr>
<td>DA0R</td>
<td>position output of right aileron actuator, degrees</td>
</tr>
<tr>
<td>DAAS</td>
<td>antisymmetric aileron deflection, degrees</td>
</tr>
<tr>
<td>DAASLN</td>
<td>component of total antisymmetric aileron deflection, linearization input only, degrees</td>
</tr>
<tr>
<td>DAASSTR</td>
<td>antisymmetric aileron deflection resulting from trim calculations, degrees</td>
</tr>
<tr>
<td>DADL</td>
<td>d/dt of left aileron, degrees/sec</td>
</tr>
<tr>
<td>DADR</td>
<td>d/dt of right aileron, degrees/sec</td>
</tr>
<tr>
<td>DAL</td>
<td>total left aileron position, includes linearization input, degrees</td>
</tr>
<tr>
<td>DALIC</td>
<td>left aileron deflection initial condition, degrees</td>
</tr>
<tr>
<td>DALLN</td>
<td>component of total left aileron deflection, linearization input only, degrees</td>
</tr>
<tr>
<td>DALLN1</td>
<td>( \text{DALLN} ) (if ( \text{not.LLNCY} )) or ( \text{DASYLN} - \text{DAASLN} ) (if ( \text{LLNCY} )).</td>
</tr>
</tbody>
</table>
DAR total right aileron position, includes linearization input, degrees
DARIC right aileron deflection initial condition, degrees
DARLN component of total right aileron deflection, linearization input only, degrees
DARLN1 = DARLN (if .not.LLNCSY) or (DASYLN + DASYLN1) (if LLNCSY).
DASY symmetric aileron deflection, degrees
DASYLN component of total symmetric aileron deflection, linearization input only, degrees
DASYTR symmetric aileron deflection resulting from trim calculations, degrees
DATMBT aileron trim button, pilot input, (1,0,-1)
DF0L position output of left trailing-edge flap actuator, degrees
DF0R position output of right trailing-edge flap actuator, degrees
DFAS antisymmetric trailing-edge flap deflection, degrees
DFASLN component of total antisymmetric trailing-edge flap deflection, linearization input only, degrees
DFASTR antisymmetric trailing-edge flap deflection resulting from trim calculations, degrees
DFDL d/dt of left trailing-edge flap, degrees/sec
DFDR d/dt of right trailing-edge flap, degrees/sec
DFL total left trailing-edge flap position, includes linearization input, degrees
DFLIC left trailing-edge flap deflection initial condition, degrees
DFLLN component of total left trailing-edge flap deflection, linearization input only, degrees
DFLLN1 = DFLLN (if .not.LLNCSY) or (DFSYLN - DFASLN) (if LLNCSY).
DFR total right trailing-edge flap position, includes linearization input, degrees
DFRIC right trailing-edge flap deflection initial condition, degrees
DFRLN component of total right trailing-edge flap deflection, linearization input only, degrees
DFRLN1 = DFRLN (if .not.LLNCSY) or (DFSYLN + DFASLN) (if LLNCSY).
DFSY symmetric trailing-edge flap deflection, degrees
DFSYLN component of total symmetric trailing-edge flap deflection, linearization input only, degrees
DFSYTR symmetric trailing-edge flap deflection resulting from trim calculations, degrees
DG2RA degrees to radians conversion, (\pi/180)
DLG landing gear deployment; assumes values in the interval [0.0,1.0] where 0.0 represents full up, and 1.0 represents full down. Default is full up.
DLGPCT % DLG, (AOA probe)
DLTVCL left overall thrust vectoring vane deflection command, degrees
DLTVCR right overall thrust vectoring vane deflection command, degrees
DN0L position output of left leading-edge flap actuator, degrees
DN0R position output of right leading-edge flap actuator, degrees
DNAS antisymmetric leading-edge flap deflection, degrees
DNASLN component of total antisymmetric leading-edge flap deflection, linearization input only, degrees
DNASTR antisymmetric leading-edge flap deflection resulting from trim calculations, degrees
DN0L d/dt of left leading-edge flap, degrees/sec
DN0R d/dt of right leading-edge flap, degrees/sec
DNL total left leading-edge flap position, includes linearization input, degrees
DNLIC left leading-edge flap deflection initial condition, degrees
DNLLN component of total left leading-edge flap deflection, linearization input only, degrees
DNLLN1 = DNLLN (if .not.LLNCSY) or (DNSYNL + DNASLN) (if LLNCSY).
DNR total right leading-edge flap position, includes linearization input, degrees
DNRIC right leading-edge flap deflection initial condition, degrees
DNRLN component of total right leading-edge flap deflection, linearization input only, degrees
DNRLN1 = DNRLN (if .not.LLNCSY) or (DNSYNL + DNASLN) (if LLNCSY).
A.8

DNSY  symmetric leading-edge flap deflection, degrees
DNSYLN component of total symmetric leading-edge flap deflection, linearization input only, degrees
DNSYTR symmetric leading-edge flap deflection resulting from trim calculations, degrees
DPASLN component of total antisymmetric power lever angle input, linearization only, degrees
DPASTR antisymmetric power lever angle deflection resulting from trim calculations, degrees
DPLDL \( \frac{d}{dt} \) of left throttle boost output signal, degrees/sec
DPLDR \( \frac{d}{dt} \) of right throttle boost output signal, degrees/sec
DPLL left throttle boost output signal, degrees
DPLLIC left throttle boost output signal initial condition, degrees
DPLLNN added to DPLL, linearization input only, degrees
DPLLNN1 = DPLLNN (if \( \text{not.LLNCSY} \)) or (DPSYLN - DPASLN) (if LLNCSY).
DPLR right throttle boost output signal, degrees
DPLRIC right throttle boost output signal initial condition, degrees
DPRLN added to DPPL, linearization input only, degrees
DPRLNN1 = DPRLN (if \( \text{not.LLNCSY} \)) or (DPSYLN + DPASLN) (if LLNCSY).
DPSYLN component of total symmetric throttle boost output signal, linearization input only, degrees
DPSYTR symmetric power lever angle deflection resulting from trim calculations, degrees
DROL position output of left rudder actuator, degrees
DROR position output of right rudder actuator, degrees
DRAS antisymmetric rudder deflection, both t.e. left, degrees
DRASLN component of total antisymmetric rudder deflection, linearization input only, degrees
DRASTR antisymmetric rudder deflection resulting from trim calculations, degrees
DRDL \( \frac{d}{dt} \) of left rudder, degrees/sec
DRDR \( \frac{d}{dt} \) of right rudder, degrees/sec
DRL total left rudder position (pos t.e.left), includes linearization input, degrees
DRLIC left rudder deflection initial condition, degrees
DRLNN = DRLNN (if \( \text{not.LLNCSY} \)) or (DRSYLN - DRASLN) (if LLNCSY).
DRLR total right rudder position (pos t.e.left), includes linearization input, degrees
DRLRIC right rudder deflection initial condition, degrees
DRLRLN component of total right rudder deflection, linearization input only, degrees
DRLRLN1 = DRLRLN (if \( \text{not.LLNCSY} \)) or (DRSYLN + DRASLN) (if LLNCSY).
DRS symmetric rudder deflection, both t.e. in, degrees
DRSYPN component of total symmetric rudder deflection, linearization input only, degrees
DRSYTR symmetric rudder deflection resulting from trim calculations, degrees
DSOL position output of left stabilator actuator, degrees
DSOR position output of right stabilator actuator, degrees
DSAS antisymmetric stabilator deflection, degrees
DSASLN component of total antisymmetric stabilator deflection, linearization input only, degrees
DSASTR antisymmetric stabilator deflection resulting from trim calculations, degrees
DSB speed brake deflection, degrees
DSBD \( \frac{d}{dt} \) DSB, degrees/sec
DSBIC initial condition for DSB, degrees
DSBLN component of total speed brake deflection, linearization input only, degrees
DSDL \( \frac{d}{dt} \) of left stabilator, degrees/sec
DSDLNN component of total left stabilator position, includes linearization input, degrees
DSL component of total left stabilator deflection initial condition, degrees
DSLIC left stabilator deflection initial condition, degrees
DSLNN component of total left stabilator deflection, linearization input only, degrees
DSLLN = DSLLN (if .not.LLNCSY) or (DSSYLN - DSASLN) (if LLNCSY).
DSR = total right stabilator position, includes linearization input, degrees
DSRIC = right stabilator deflection initial condition, degrees
DSRLN = component of total right stabilator deflection, linearization input only, degrees
DSRLN1 = DSRLN (if .not.LLNCSY) or (DSSYLN + DSASLN) (if LLNCSY).
DSSY = symmetric stabilator deflection, degrees
DSSYLN = component of total symmetric stabilator deflection, linearization input only, degrees
DSSYTR = symmetric stabilator deflection resulting from trim calculations, degrees
DSTMBT = pilot stick pitch trim button
DTVOLL = lower left thrust vectoring vane deflection, actuator output, degrees
DTVOLU = upper left thrust vectoring vane deflection, actuator output, degrees
DTVORL = lower right thrust vectoring vane deflection, actuator output, degrees
DTVORU = upper right thrust vectoring vane deflection, actuator output, degrees
DTVDLL = d/dt of lower left thrust vectoring vane deflection, degrees/sec
DTVDLU = d/dt of upper left thrust vectoring vane deflection, degrees/sec
DTVDRL = d/dt of lower right thrust vectoring vane deflection, degrees/sec
DTVDRU = d/dt of upper right thrust vectoring vane deflection, degrees/sec
DTVL = total left engine thrust vectoring vane deflection, degrees
DTVLL = left lower thrust vectoring vane deflection, degrees
DTVLLN = added to total left engine thrust vectoring vane deflection, linearization input only, degrees
DTVLU = left upper thrust vectoring vane deflection, degrees
DTVLR = total left engine thrust vectoring vane deflection, degrees
DTVRL = right lower thrust vectoring vane deflection, degrees
DTVRLN = added to total right engine thrust vectoring vane deflection, linearization input only, degrees
DTVRU = right upper thrust vectoring vane deflection, degrees
DX1 = intermediate variable in pressure sensor function calculations
DX2 = intermediate variable in pressure sensor function calculations
E0 = quaternion, n.d.
E00 = E0 prior to normalization
E000 = Direct integral of E0D = d/dt E0
E02 = E0**2, used in direction cosine calculations
E0D = d/dt of E0, = .5*(-E1*P-E2*Q-E3*R), rad/sec
E0IC = Initial condition for E0, derived from trim Euler angles
E1 = quaternion, n.d.
E10 = E1 prior to normalization
E100 = Direct integral of E1D = d/dt E1
E12 = E1**2, used in direction cosine calculations
E1D = d/dt of E1, = .5*( E0*P-E3*Q+E2*R), rad/sec
E1IC = Initial condition for E1, derived from trim Euler angles
E2 = quaternion, n.d.
E20 = E2 prior to normalization
E200 = Direct integral of E2D = d/dt E2
E22 = E2**2, used in direction cosine calculations
E2D = d/dt of E2, = .5*( E3*P+E0*Q-E1*R), rad/sec
E2IC = Initial condition for E2, derived from trim Euler angles
E3 = quaternion, n.d.
E30 = E3 prior to normalization
E300 = Direct integral of E3D = d/dt E3
E32 = E3**2, used in direction cosine calculations
E3D = d/dt of E3, = .5*(-E2*P+E1*Q+E0*R), rad/sec
E3IC = initial condition for E3, derived from trim Euler angles
used to prevent divide by zero, $10^{-10}$

time at which dynamic check perturbation is applied, sec

FCS logical for lateral gain schedule bypass, default = .F., (DO NOT CHANGE)

FCS logical to reset lateral trim integrator, default = .F., (DO NOT CHANGE)

marker for flight control system discrete block

FCS logical for pitch forward loop gain (8.3.3 PROM set), default = .T., (DO NOT CHANGE)

=Mach number, but limited so that: $0.9 \leq \text{FGKAOA} \leq 1.4$. Used as independent variable for sensor angle-of-attack gain value look-up.

gross force produced by left engine prior to inclusion of thrust vectoring effects, lbs.

gross force produced by right engine prior to inclusion of thrust vectoring effects, lbs.

left engine thrust vectoring vane deflection angle, degrees

right engine thrust vectoring vane deflection angle, degrees

=Mach number, but limited so that: $0.0 \leq \text{FHM1} \leq 1.65$. Used as independent variable in static pressure sensor look-up.

left engine ram drag, lbs

right engine ram drag, lbs

fuselage station coordinate of the center of gravity, inches

fuselage station coordinate of the engine/airframe interface, either engine, 687.5 in.

fuselage station coordinate of the aerodynamic reference center, inches

event marker for flight test data control input discrete block

array used to hold 1 record of flight data read off a file, 50 elements.

total generalized force vector for rigid-body dynamics

aerodynamic component of FVR

thrust induced component of FVR

gravity induced component of FVR

inertial component of FVR

aerodynamic disturbance (wind and gust) component of FVR

acceleration due to gravity, 31.174 ft/sec$^2$

longitudinal flight path angle, radians

longitudinal flight path angle, degrees

target longitudinal flight path angle used in trim search, radians

GAM - GAMTR, driven to zero by trim search

candidate to prevent one component of the solution vector from reaching a solution earlier and remaining fixed. An unchanging element of solution vector will lead to a singularity in the sensitivity matrix estimation.

scaling parameter placed on a random number applied to next trim search solution

gain on left engine thrust error, VAC.

gain on right engine thrust error, VAC.

gain on left engine core dynamics. Second order filter.

gain on right engine core dynamics. Second order filter.

angle-of-attack sensor gain value.

FCS logical used in g-limit on stick input, default=.T. (DO NOT CHANGE)

desired load factor used in trim search when TCASE=3, g's

FCS logical used for g load override (TK5, TK8), default = .F. (DO NOT CHANGE)

vertical distance from sea level to aircraft c.g., ft

d/dt of H, ft/sec

vertical distance from ground to the a.r.c., ft.
HIC  initial condition for H, ft
HRF  1962 standard atmosphere altitude in feet corresponding to a given air density, ρ, in slugs/ft³
HSTORE FCS logical for heavy stores, default = .F. (DO NOT CHANGE)
I  summing index used throughout simulation
IALG integer switch to select ACSL integration algorithm:
(1) Adams-Moulton, variable step, variable order
(2) Gear's stiff; variable step, variable order
(3) Runge-Kutta 1st order or Euler
(4) Runge-Kutta 2nd order (default for this simulation)
(5) Runge-Kutta 4th order (default for ACSL)
(6) User supplied subroutine (INTEG)
(7) Runge-Kutta-Fehlberg 2nd order
(8) Runge-Kutta-Fehlberg, 5th order
IDYNCK Integer switch used to invoke dynamic check capability
(0) No disturbance input
(1) One sided pulse
(2) Doublet
(3) User defined signal, read from array SIG
II index used for sensor data tables
IN2FT conversion factor, 1/12 (ft/in)
ISENS FCS flag for sensor model
(0) sensor effects off, ideal measurements
(1) MDC sensor model (default)
ITFLG integer switch used to control program flow when trimming
ITR loop count used in inner loop of trim search. When a new candidate solution vector
is calculated, the resulting derivatives are then calculated ITRMX times. This
allows implicit loops in the trim loop to settle out. Implicit loops are caused by the
fact that accelerations are inputs the the control system that determine control
surface position. An alternate way to break the loop would be to include actuator
states in the trim vector. The trim search works best when the trim vector is kept
small.
ITRMX number of passes made through equations of motion in inner trim loop. See ITR.
Default = 6.
IXSEL integer pointer array of size NXTRMX used to select elements of trim solution
vector, XTRIM. The first NXTR elements of IXSEL select from 29 possible
independent variables. XTRIM is formed in subroutine XFORM.
IXX aircraft moment of inertia about x-body axis, slug-ft²
IXZ aircraft xz cross product of inertia, slug-ft²
IYSEL integer pointer array of size NXTRMX used to select elements to drive to zero in
the trim output vector, YTRIM. The first NYTR elements of IYSEL select from 15
possible output variables. YTRIM is formed in subroutine YFORM.
IYY aircraft moment of inertia about y-body axis, slug-ft²
IZZ aircraft moment of inertia about z-body axis, slug-ft²
J simulation summing index
KFS longitudinal stick force spring, = 7.0 lbs/in, input to FI8FCS
LAMDA difference between ground track angle and heading angle, radians
LCAASP logical switch
(.T.) A dynamic check perturbation is added to the antisymmetric aileron
command.
(.F.) no action (default)
LCASYP logical switch
A dynamic check perturbation is added to the symmetric aileron command.

**.T.** logical switch

A dynamic check perturbation is added to the antisymmetric trailing-edge flap command.

**.F.** no action (default)

**LCFASP**

A dynamic check perturbation is added to the symmetric trailing-edge flap command.

**.T.** logical switch

**LCFSYP**

A dynamic check perturbation is added to the antisymmetric leading-edge flap command.

**.F.** no action (default)

**LCNASP**

A dynamic check perturbation is added to the symmetric leading-edge flap command.

**.F.** no action (default)

**LCNSYP**

A dynamic check perturbation is added to the antisymmetric power lever angle command.

**.F.** no action (default)

**LCPASP**

A dynamic check perturbation is added to the symmetric power lever angle command.

**.F.** no action (default)

**LCPSYP**

A dynamic check perturbation is added to the antisymmetric rudder command.

**.F.** no action (default)

**LCRASP**

A dynamic check perturbation is added to the symmetric rudder command.

**.F.** no action (default)

**LCRSYP**

A dynamic check perturbation is added to the antisymmetric stabilator command.

**.F.** no action (default)

**LCSSYP**

A dynamic check perturbation is added to the symmetric stabilator command.

**.F.** no action (default)

**LCSBP**

A dynamic check perturbation is added to the speed brake command.

**.F.** no action (default)

**LCSSYP**

Extended debugging output is written to unit PRN for each call to the aerodynamic coefficient calculations.

**.T.** logical switch

**LDBA**

Extended debugging output is written to unit PRN for each calculation of the inertial components of the generalized force vector and mass matrix.

**.F.** no action (default)

**LDBMI**

Logical switch - primary simulation debugging logical

**LDBOUT**

Switch - used for debugging aerodynamic calculations.

**.F.** no action (default)

**LDBA**

Switch - used for inertial effects calculation debugging.

**.F.** no action (default)

**LDBMI**
(T.) Extended ACSL debugging output is written to unit PRN after the trim search or when time reaches TSTP.

(F.) no action (default)

LDBSS  logical switch - debugging logical for the subroutine that calculates the accelerations by solving the vector equation $[M][a] = \{f\}$

(T.) Debugging output is written to unit PRN from subroutine XRBVDC.

(F.) no action (default)

LDBTR  logical switch - used for debugging failed trim attempts.

(T.) Each new solution trial, XTRIM, and the resulting YTRIM vector are written to unit=6 (typically the screen) and also unit=PRN

(F.) no action (default)

LEULER logical switch:

(T.) Euler angles rates are integrated directly.

(F.) quaternion derivatives are integrated. (default)

LFCS  logical switch - enables flight control system - read in from file "f18tr.dat"

(T.) FCS on (default)

(F.) FCS off

LFTD logical switch - enables use of flight data to drive control surface deflections

(T.) Control deflections set to data in FTDAT. Actuators bypassed.

(F.) Normal simulation operation. (default)

LLDR logical switch

(T.) When START command is executed, initial conditions for all possible XTRIM variables are read in from file "f18tr.dat". The default on the first execution of START is .T. Reset to .F. after "f18tr.dat" is read in.

(F.) no action

LLIMDF  logical switch

(T.) Assign hardwired values to array of upper and lower bounds on elements of XTRIM variables. Trim algorithm confines search to this space. The hardwired values are defined in array DEFLIM in subroutine TRIM.

(F.) Use limit values read from "f18tr.dat" file. (default)

LLNCSY logical switch, used to control the 'LN' exogenous inputs that can be created to support the 'ANALYZ' command in ACSL. Dictates whether the exogenous inputs available to the ANALYZ option, which are used to calculate _LN1 inputs, are symmetric/antisymmetric quantities or right/left quantities.

(T.) _LN1 = _SYLN + _ASLN (default)

(F.) _LN1 = _LN where _LN1 is summed with actual control surface position in degrees. Examples of _LN1 variables and DSRLN1 (left stabilator), DSLLN1 (right stabilator), and DRLLN1 (left rudder).

LPCAP logical switch

(T.) Put dynamic check perturbation on lateral stick input.

(F.) no action (default)

LPCRP logical switch

(T.) Put dynamic check perturbation on rudder pedal input.

(F.) no action (default)

LPCSP logical switch

(T.) A dynamic check perturbation is added to the longitudinal stick.

(F.) no action (default)

LQSE logical switch - passed to subroutine SFAERRF and USAERRF - used to enable/disable the quasi-static-elastic (QSE) modeling option in the aerodynamic model
(T) normal QSE aerodynamics. All flex/rigid ratios and increments apply.
(default)
(F) All flex/rigid ratios and increments are set to limiting value as altitude
becomes large or density goes to zero.

**LRDFTI**
logical switch - used to drive control surface positions according to a data file - as
would occur with flight test data
(T) Subroutine FTDRDF is called. Data is read from file="mhftdi.dat".
(F) no action (default)

**LRDWR**
internal integer switch - intermediate flow control switch set in the simulation and
used to control action in call to subroutine RDWRTR - can not be set by runtime
commands
(1) causes f18tr.dat trim file to be read in (default)
(2) causes f18tr.dat trim file to be written on

**LRTE**
logical switch - passed to subroutine SFAERRF - used when conducting
comparisons to recover the form of the aerodynamic model found in the original
DMS simulation
(T) activates form of subroutine SFAERRF that agrees with
dmsf18 math model (default)
(F) activates changes discussed in section 5.1 - aerodynamic model

**LTHCGL**
left engine thrust moment about body frame x-axis at c.g., ft-lbs

**LTHCGR**
right engine thrust moment about body frame x-axis at c.g., ft-lbs

**LTHDMS**
logical switch - used to duplicate the DMS throttle position
(T) use DMS scaled throttle position
(F) normal MDC F18 throttle position (default)

**LTHVEC**
logical switch - used to invoke preliminary thrust-vectored engine model
(T) preliminary thrust-vectored engine model (default)
(F) non-thrust-vectored engine model

**LTR**
logical switch
(T) Trim search is initiated after runtime START command. If trim fails, TSTP
set = 0. (default)
(F) No trim attempted. Integration proceeds with current i.c.'s until T=TSTP.

**LTRFLG**
internal logical switch - used to indicate current TRIM status
(T) simulation in trim search loop
(F) not in trim search loop

**LVDEF**
logical flag - used to obtain extended output with variable definitions form
dictionary
(T) All simulation variable values printed out onto unit=PRN with dictionary
definitions taken from unit=29.
(F) no action (default)

**LWRFTO**
logical switch - used for FLT data comparison
(T) subroutine FTDWRF called - data written to file="ftifo.dat"
(F) no action (default)

**LWRTR**
logical switch - used to write new file "f18tr.dat"
(T) Write the next calculated trim values to file "f18tr.dat". Set LWRTR to .F.
(F) no action (default)

**MACH**
Mach number, n.d.

**MACHRF**
Free-stream Mach number at a.r.c., n.d.

**MACHTR**
Mach number to be achieved in trim search if "1" is in the active IXSEL list, n.d.

**MARR**
aerodynamic component of rigid-rigid quadrant of mass matrix

**MASS**
aircraft mass, slugs

**MINT**
minimum integration step size (default value supplied by ACSL)

**MIRR**
inertial component of rigid-rigid quadrant of a mass matrix

**MMRR**
total rigid-rigid quadrant of a mass matrix

**MNSPIN**
FCS logical spin switch. Default = .F. (DO NOT CHANGE).
left engine thrust moment about body frame y-axis at c.g., ft-lbs.
right engine thrust moment about body frame y-axis at c.g., ft-lbs.
bank angle in degrees sought in trim search if "29" included in active IXSEL list.
Will produce coordinated turn if TCASE = 2.

In the fl8bas trim strategy (section 2.2), MUTRMX is equivalent to variable "MUMAX" in ACSL TRIM algorithm (see section 5.2.1, ACSL REFERENCE MANUAL REV. 4.1) - default = 10

maximum number of iterations for simulation trimming scheme - default = 80
maximum integration step size - default = 0.00625 seconds
square root of sum of squares of quaternion intermediate states, used to normalize quaternions at each time step to prevent numerical problems - n.d
minimum number of integration steps in a communication interval. Default = 1.
This allows integration step size to be controlled by MXSTP as per recommendation in ACSL manual.

left engine thrust yaw moment about body z-axis at c.g. (TV), ft-lbs
right engine thrust yaw moment about body z-axis at c.g. (TV), ft-lbs
integer switch - FCS flag for thrust vector pitch control blend (1=ON). Default = 1.
number of independent variables for simulation trim search (=NXTRMX)
maximum number of independent variables for simulation trim search (10)
3 element array describing location of n_y accelerometer in FS/BL/WL coordinates, inches

lateral acceleration sensor signal, g's
number of dependent variables for simulation trim algorithm (=NXTR)
normal acceleration sensor signal, g's
normal acceleration 1-g steady state removed. NZZR = - AZ - 1. g's
FCS logical to override angle-of-attack limiter. Default = .F. (DO NOT CHANGE).

body axis roll rate, rad/sec
gain in left core engine dynamics. 2nd order filter.
gain in right core engine dynamics. 2nd order filter
gain in left core engine dynamics. 2nd order filter
gain in right core engine dynamics. 2nd order filter
Integer that defines page size as number of lines. (45 for NOS, 55 for VAX)
pilot lateral stick position, inches
pilot lateral stick position from flight test data, inches
pilot lateral stick position signal array for IDYNCK=3
pilot lateral stick position required for trim, inches.
pilot rudder pedal force, lbs
pilot rudder pedal force from flight test data, lbs
pilot rudder pedal force signal array for IDYNCK=3
pilot rudder pedal force required for trim, lbs
pilot longitudinal stick position, inches
pilot longitudinal stick position flight test data, inches
pilot longitudinal stick position signal array for IDYNCK=3
pilot longitudinal stick position required for trim, inches
body axis roll acceleration, rad/sec^2
body axis roll rate, degrees/second
gain on dynamic check perturbation command
Euler roll angle, radians
Euler roll angle intermediate state, integral of PHID
Euler roll angle rate of change, rad/sec
Euler roll angle, degrees
<table>
<thead>
<tr>
<th>Variable</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>PHILN</td>
<td>Euler roll angle linearization dummy variable, radians</td>
</tr>
<tr>
<td>PHITR</td>
<td>Euler roll angle required for trim, radians</td>
</tr>
<tr>
<td>PHIZR</td>
<td>Euler roll angle referenced to &quot;PHITR&quot;, radians</td>
</tr>
<tr>
<td>PIC</td>
<td>body axis roll initial condition, rad/sec</td>
</tr>
<tr>
<td>PLAL</td>
<td>left engine total throttle position (power level angle), degrees</td>
</tr>
<tr>
<td>PLAR</td>
<td>right engine total throttle position (power level angle), degrees</td>
</tr>
<tr>
<td>PLDL</td>
<td>left throttle boost output error term.</td>
</tr>
<tr>
<td>PLDR</td>
<td>right throttle boost output error term.</td>
</tr>
<tr>
<td>PRN</td>
<td>high volume output goes to unit=PRN. Passed to Fortran subroutines that write to an output file. Default = 9.</td>
</tr>
<tr>
<td>PS</td>
<td>sensed roll rate, */sec, = PS0 (if ISENS=0) or = PS1 (if ISENS=1)</td>
</tr>
<tr>
<td>PS0</td>
<td>actual roll rate, */sec</td>
</tr>
<tr>
<td>PS1</td>
<td>output of rate sensor model, */sec</td>
</tr>
<tr>
<td>PSI</td>
<td>Euler yaw angle, radians</td>
</tr>
<tr>
<td>PSI0</td>
<td>Euler yaw angle intermediate state, integral of PSID</td>
</tr>
<tr>
<td>PSID</td>
<td>Euler yaw angle rate of change, rad/sec</td>
</tr>
<tr>
<td>PSIDG</td>
<td>Euler yaw angle, degrees</td>
</tr>
<tr>
<td>PSILN</td>
<td>Euler yaw angle rate linearization dummy variable, radians. [Constant]</td>
</tr>
<tr>
<td>PSITR</td>
<td>Euler yaw angle required for trim, radians</td>
</tr>
<tr>
<td>PSTATC</td>
<td>static atmospheric pressure, = f(H), PSF</td>
</tr>
<tr>
<td>PSTS</td>
<td>output of static atmospheric pressure sensor, PSF.</td>
</tr>
<tr>
<td>PSTS0</td>
<td>value assigned to PSTS if ISENS=0 (Ideal sensors).</td>
</tr>
<tr>
<td>PSTS1</td>
<td>value assigned to PSTS if ISENS=1 (Sensor model #1)</td>
</tr>
<tr>
<td>PT</td>
<td>intermediate variable in compressible pressure computation</td>
</tr>
<tr>
<td>PTI</td>
<td>intermediate variable in compressible pressure computation</td>
</tr>
<tr>
<td>PTURB</td>
<td>perturbation value used for pulse or double signal if IDYNCK=1 OR 2. Default=0.</td>
</tr>
<tr>
<td>PW</td>
<td>wind axis roll rate, rad/sec</td>
</tr>
<tr>
<td>PWDG</td>
<td>wind axis roll rate, */sec</td>
</tr>
<tr>
<td>Q</td>
<td>body axis pitch rate, rad/sec</td>
</tr>
<tr>
<td>QBAR</td>
<td>aircraft dynamic pressure, ( \tilde{q} ), lbs/ft(^2)</td>
</tr>
<tr>
<td>QBARS</td>
<td>intermediate variable, = ( \tilde{q}_S ), lbs</td>
</tr>
<tr>
<td>QBARSC</td>
<td>intermediate variable, = ( \tilde{q}_{Sb} ), lbs</td>
</tr>
<tr>
<td>QC</td>
<td>compressible impact pressure, PSF</td>
</tr>
<tr>
<td>QCDA</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDB</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDC</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDD</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDE</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCF</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDG</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCDH</td>
<td>function used in compressible impact pressure computation</td>
</tr>
<tr>
<td>QCIS</td>
<td>output of compressible pressure sensor model, PSF</td>
</tr>
<tr>
<td>QCIS0</td>
<td>compressible pressure--ideal sensor, PSF</td>
</tr>
<tr>
<td>QCIS1</td>
<td>compressible pressure--sensor model #1, PSF</td>
</tr>
<tr>
<td>QCX</td>
<td>intermediate value in sensed compressible pressure computation</td>
</tr>
<tr>
<td>QD</td>
<td>body axis pitch acceleration, rad/sec(^2)</td>
</tr>
<tr>
<td>QDG</td>
<td>body axis pitch rate, */sec</td>
</tr>
<tr>
<td>QIC</td>
<td>body axis pitch rate initial condition, rad/sec</td>
</tr>
<tr>
<td>QS</td>
<td>sensed pitch rate, */sec, = QS0 or =QS1 based on &quot;ISENS&quot;</td>
</tr>
<tr>
<td>QS0</td>
<td>actual pitch rate, */sec</td>
</tr>
</tbody>
</table>
output of rate gyro model, /sec
wind axis pitch rate, rad/sec
wind axis pitch rate, /sec
body axis yaw rate, /sec
radians to degrees conversion factor, /rad
body axis yaw acceleration, rad/sec^2
body axis yaw rate, /sec
air density, slugs/ft^3
air density at sea level, 0.00237688 slugs/ft^3
body axis yaw rate initial condition, rad/sec
ratio of actual air density to RHOSL, n.d.
sensed yaw rate, /sec, = RS0 OR =RS1 based on "ISENS"
actual yaw rate, /sec
output of rate gyro model, /sec
limited left afterburner thrust rate of change, lbs/sec
limited right afterburner thrust rate of change, lbs/sec
left engine core spool-up/-down rate lower limit, = -5500 lbs/sec
right engine core spool-up/-down rate lower limit, = -5500 lbs/sec
left engine core spool-up/-down rate upper limit, = 5500 lbs/sec
right engine core spool-up/-down rate upper limit, = 5500 lbs/sec
wind axis yaw rate, rad/sec
wind axis yaw rate, /sec
error term between speed brake position and command, degrees
speed brake no load rate limit, = 60/2.5, degrees/second
set thrust vectoring differential command, input to subroutine F18FCS, default = -101. [Constant]
set thrust vectoring symmetric command, input to subroutine F18FCS, default = -101. [Constant]
array of input values, in order of increasing time. Use SIG for open loop control surface deflections independent of simulated pilot input
SIG(1 ->100) = Signal amplitude values
SIG(101->200) = Time breakpoint of corresponding amplitude values
value of throttle signal at current time, = CSPYSG(T)
value of generic signal at current time, = SIG(T)
value of lateral stick signal at current time, = PCASG (T)
value of rudder pedal signal at current time, = PCRSG (T)
value of longitudinal stick signal at current time, = PCSSG (T)
sin(α = angle of attack at c.g.)
sin(α_ref = angle of attack at a.r.c.)
sine of azimuth angle of installed left engine n.d.
sine of azimuth angle of installed right engine n.d.
sin(β = sideslip angle at c.g.)
sin(obl)
sin( PHITR / 2 ), n.d.
sin( PSITR / 2 ), n.d.
sin( THETA ), n.d.
sin( THETR / 2 ), n.d.
sine of thrust-vectoring vane orientation angle, n.d.
sensed static pressure gain value
FCS logical for stores logic (default = F.) (DO NOT CHANGE).
aerodynamic (wing) reference area, 400 ft$^2$

time, sec

temporary variable used in rotational acceleration equations, $= IXX*P - IXZ*R$

temporary variable used in rotational acceleration equations, $= IYY*Q$

temporary variable used in rotational acceleration equations, $= - IXZ*P + IZZ*R$

left afterburner thrust, lbs

left afterburner thrust initial condition, lbs

right afterburner thrust, lbs

right afterburner thrust initial condition, lbs

$\tan(\theta)$

minimum engine thrust with afterburner engaged, lbs

maximum engine thrust with afterburner engaged, lbs

left engine time constant for VAH first order lag dynamics

saved value of TAUL from last time in core engine dynamics

right engine time constant for VAH first order lag dynamics

saved value of TAUR from last time in core engine dynamics

integer switch to determine trim solution sought

(1) no action - used for normal wings-level trim

(2) $p,q,r$ set to values required for coordinated turn at selected bank angle in degrees, MUDGTR

(3) $q$ set to value required for symmetric pull-up at load factor in $g$'s selected by GLOAD

coefficient $= QBAR / 100$

test value for left engine core dynamic nonlinear switch logic

test value for right engine core dynamic nonlinear switch logic

total engine thrust for thrust vectored engine, lbs

Euler pitch angle, radians

Euler pitch angle intermediate state, integral of THED

Euler pitch angle rate of change, rad/sec

Euler pitch angle, degrees

Euler pitch angle linearization dummy variable, radians

Euler pitch angle rate required for trim, radians

left engine net thrust, lbs

left engine net thrust intermediate state, lbs

$= TTL$ if in military power range

$= TABL$ if in afterburner

left engine thrust linearization dummy variable, lbs

right engine net thrust, lbs

right engine net thrust intermediate state, lbs

$= TTR$ if in military power range

$= TABR$ if in afterburner

thrust command sent to left engine, lbs

thrust command sent to right engine, lbs

left engine reference thrust. $< 0$ if in afterburner dynamics, lbs

right engine reference thrust. $< 0$ if in afterburner dynamics, lbs

right engine thrust linearization dummy variable, lbs

left engine net thrust component in x-direction (NTV), lbs

right engine net thrust component in x-direction (NTV), lbs

left engine net thrust component in y-direction (NTV), lbs

right engine net thrust component in y-direction (NTV), lbs

left engine net thrust component in z-direction (NTV), lbs

right engine net thrust component in z-direction (NTV), lbs

engine thrust at idle throttle setting, lbs
TML  maximum military thrust, lbs
TNETL  miscellaneous output - left engine net thrust (TV), lbs
TNETR  miscellaneous output - right engine net thrust (TV), lbs
TRTOL  convergence requirement for successful trim - default = 0.00005
TSFCS  time interval at which flight control system discrete is invoked, seconds
TSFID  time interval between flight test data points, sec
TSOTP  simulation stop time - default = 0.0 seconds
TT  total thrust from left and right engine thrust, lbs
TTL  sum of left engine thrust terms VAKL & VAFL (NTV), lbs
TTR  sum of right engine thrust terms VAKL & VAFL (NTV), lbs
TVDBOT  FCS logical. Used to removed thrust vectoring deadband. Makes trimming possible when thrust vectoring is selected. Default = .T.
TVLLIC  CTVLL initial condition
TVLUIC  CTVLU initial condition
TVOA  thrust - vectoring vane orientation angle, degrees
TVRLIC  CTVRL initial condition
TVRUIC  CTVRU initial condition
U  body axis inertial velocity in x-body direction, ft/sec
UA  body axis atmospheric velocity in x-body direction, ft/sec
UA2  UA squared, ft²/sec²
UARF  UA at a.r.c., ft/sec
UD  body axis inertial acceleration in x-direction, ft/sec²
UDA  d/dt of UA, ft/sec²
UDWG  d/dt of aerodynamic disturbance component in x-body axis, ft/sec²
UIC  body axis inertial velocity in x-direction i.c., ft/sec
UWG  x-body component of aerodynamic disturbance velocity, ft/sec
V  body axis inertial velocity in y-body direction, ft/sec
VA  body axis atmospheric velocity in y-body direction, ft/sec
VA2  VA squared, ft²/sec²
VAEL  rate-limited left engine spool-up/-down intermediate state, lbs/sec
VAERIC  rate-limited right engine spool-up/-down intermediate state, lbs/sec
VAEDL  artificial fast derivative inserted to achieve explicit formulation, the integral of which is VAEOL
VAEDR  artificial fast derivative inserted to achieve explicit formulation, the integral of which is VAEOR
VAELIC  rate-limited left engine spool-up/-down initial condition, lbs/sec
VAER  rate-limited right engine spool-up/-down , lbs/sec
VAERIC  rate-limited right engine spool-up/-down initial condition, lbs/sec
VAFL  main component of left engine core dynamics, lbs
VAFLIC  main component of left engine core dynamics initial condition, lbs
VAFR  main component of right engine core dynamics, lbs
VAFRIC  main component of right engine core dynamics initial condition, lbs
VAHL  output of left engine core dynamics nonlinear switch, lbs
VAHLS  saved value of VAHL from last time in core engine dynamic
VAHR  output of right engine core dynamics nonlinear switch, lbs
VAHRS  saved value of VAHR from last time in core engine dynamic
VAK1DL  intermediate left core engine dynamic, saved past value, lbs/sec
VAK1DR  intermediate right core engine dynamic, saved past value, lbs/sec
VAKDDL  left core engine spool up input, lbs/sec²
VAKDDR  right core engine spool up input, lbs/sec²
VAKDL   intermediate left core engine dynamic, lbs/sec
VAKDR   intermediate right core engine dynamic, lbs/sec
VAKL    output of left engine core 2nd order dynamics, lbs
VAKLIC  initial condition of integrator for VAKL
VAKR    output of right engine core 2nd order dynamics, lbs
VAKRIC  initial condition of integrator for VAKR
VARF   VA at a.r.c., ft/sec
VD    body axis inertial acceleration in y-direction, ft/sec²
VDA    d/dt of VA, ft/sec²
VDBA   deadband applied to thrust vectoring vane deflection, radians
VDWG   d/dt of aerodynamic disturbance component in y-body axis, ft/sec²
VGS    aircraft ground speed, ft/sec
VHIDL   VH1L rate of change, lbs/sec
VHIDR   VH1R rate of change, lbs/sec
VHIL    left engine state created by 1st order lag mechanization, lbs
VHILIC  left engine core thrust at initial condition, lbs
VHILS   saved value of 'VHIL' from last time in core engine dynamic, lbs
VH1R    right engine state created by 1st order lag mechanization, lbs
VH1RIC  right engine core thrust at initial condition, lbs
VH1RS   saved value of 'VH1R' from last time in core engine dynamic, lbs
VIC    body axis inertial velocity in y-direction i.c., ft/sec
VKDLIC  initial condition on first integral in left core engine dynamic, lbs/sec²
VKDRIC  initial condition on first integral in right core engine dynamic, lbs/sec²
VS    speed of sound, ft/sec
VT    aircraft total atmosphere velocity, ft/sec
VTD    aircraft total atmosphere acceleration, ft/sec²
VTINV  coefficient to normalize by total velocity, sec/ft
VTRF   total airspeed at a.r.c., ft/sec
VTRINV  coefficient to normalize by total velocity at a.r.c., sec/ft
VTR    aircraft total atmosphere velocity after successful trim, ft/sec
VWG    y-body component of aerodynamic disturbance velocity, ft/sec
W    body axis inertial velocity in z-body direction, ft/sec
WA    body axis atmospheric velocity in z-body direction, ft/sec
WA2    WA squared, ft²/sec²
WARF   WA at a.r.c., ft/sec
WD    body axis inertial acceleration in z-direction, ft/sec²
WDA    (d/dt) of WA, ft/sec²
WDWG   d/dt of aerodynamic disturbance component in z-body axis, ft/sec²
WFL    left engine fuel flow
WFR    right engine fuel flow
WIC    body axis inertial velocity in z-direction i.c., ft/sec
WIDTH  time span to hold step input dynamic check perturbation command, default = 1.0 seconds
WLCG   water line coordinate of the center of gravity, inches
WLENG  water line coordinate of the engine/airframe interface, right/left engine, 100.0 in.
WLRFC  water line coordinate of the aerodynamic reference center, = 100.0 inches
WT    aircraft weight, lbs
WWG    z-body component of aerodynamic disturbance velocity, ft/sec
XALF   air data probe alpha with source noise added, degrees
XARF   x-direction distance from c.g. to a.r.c., ft

A.20
<table>
<thead>
<tr>
<th>Variable</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>XBAR</td>
<td>normalized x-location of accelerometer from c.g., n.d.</td>
</tr>
<tr>
<td>XD</td>
<td>aircraft inertial ground track velocity in track direction, ft/sec</td>
</tr>
<tr>
<td>XDDWG</td>
<td>d/dt of XDWG, ft/sec²</td>
</tr>
<tr>
<td>XDWG</td>
<td>aerodynamic disturbance velocity component in x-earth frame direction, ft/sec</td>
</tr>
<tr>
<td>XDWGIC</td>
<td>aerodynamic disturbance velocity component in x-earth frame direction - initial condition, ft/sec</td>
</tr>
<tr>
<td>XHM1</td>
<td>sensed static pressure breakpoint vector</td>
</tr>
<tr>
<td>XRFCG</td>
<td>'x' component of the location of right (left) engine/airframe interface point in c.g.-centered body frame, = -(FSENG - FSCG)/12., ft.</td>
</tr>
<tr>
<td>XTHCG</td>
<td>total thrust force at c.g. in body x-direction (TV), lbs</td>
</tr>
<tr>
<td>XTHCGL</td>
<td>left engine thrust force at c.g. in body x-direction (TV), lbs</td>
</tr>
<tr>
<td>XTHCGR</td>
<td>right engine thrust force at c.g. in body x-direction (TV), lbs</td>
</tr>
<tr>
<td>XTRLM</td>
<td>2 by 30 array with upper and lower limits on XTRIM independent variables</td>
</tr>
<tr>
<td>XTVL</td>
<td>left engine thrust force in body x-direction (TV), lbs</td>
</tr>
<tr>
<td>XTVR</td>
<td>right engine thrust force in body x-direction (TV), lbs</td>
</tr>
<tr>
<td>YARF</td>
<td>y-direction distance from c.g. to a.r.c., ft</td>
</tr>
<tr>
<td>YBAR</td>
<td>normalized y-location of accelerometer from c.g., n.d.</td>
</tr>
<tr>
<td>YD</td>
<td>aircraft inertial ground track velocity in crosstrack direction, ft/sec</td>
</tr>
<tr>
<td>YDDWG</td>
<td>d/dt of YDWG, ft/sec²</td>
</tr>
<tr>
<td>YDWG</td>
<td>aerodynamic disturbance velocity component along earth frame y-axis, ft/sec</td>
</tr>
<tr>
<td>YDWGIC</td>
<td>aerodynamic disturbance velocity component along earth frame y-axis - initial condition, ft/sec</td>
</tr>
<tr>
<td>YGKAO2</td>
<td>sensed angle-of-attack gain table</td>
</tr>
<tr>
<td>YGKAOA</td>
<td>sensed angle-of-attack gain table</td>
</tr>
<tr>
<td>YRFCGL</td>
<td>'y' component of the location of left engine/airframe interface point in c.g.-centered body frame, = (BLENGL - BLCG)/12., ft.</td>
</tr>
<tr>
<td>YRFCGR</td>
<td>'y' component of the location of right engine/airframe interface point in c.g.-centered body frame, = (BLENGR - BLCG)/12., ft.</td>
</tr>
<tr>
<td>YSAS</td>
<td>FCS logical for yaw SAS on. Default = .T. (DO NOT CHANGE)</td>
</tr>
<tr>
<td>YTHCGL</td>
<td>left engine thrust force at c.g. in body y-direction (TV), lbs</td>
</tr>
<tr>
<td>YTHCGR</td>
<td>right engine thrust force at c.g. in body y-direction (TV), lbs</td>
</tr>
<tr>
<td>YTVL</td>
<td>left engine thrust force at nozzle in y-body direction (TV), lbs</td>
</tr>
<tr>
<td>YTVR</td>
<td>right engine thrust force at nozzle in y-body direction (TV), lbs</td>
</tr>
<tr>
<td>ZARF</td>
<td>z-direction distance from c.g. to a.r.c., ft</td>
</tr>
<tr>
<td>ZBAR</td>
<td>normalized z-location of accelerometer from c.g., n.d.</td>
</tr>
<tr>
<td>ZDDWG</td>
<td>(d/dt) of ZDWG, ft/sec²</td>
</tr>
<tr>
<td>ZDWG</td>
<td>aerodynamic disturbance velocity component along earth frame z-axis, ft/sec</td>
</tr>
<tr>
<td>ZDWGIC</td>
<td>aerodynamic disturbance velocity component along earth frame z-axis - initial condition, ft/sec</td>
</tr>
<tr>
<td>ZRFCG</td>
<td>'z' component of the location of right (left) engine/airframe interface point in c.g.-centered body frame, = -(WLENG - WLCG)/12., ft.</td>
</tr>
<tr>
<td>ZTHCGL</td>
<td>left engine thrust force at c.g. in body z-direction (TV), lbs</td>
</tr>
<tr>
<td>ZTHCGR</td>
<td>right engine thrust force at c.g. in body z-direction (TV), lbs</td>
</tr>
<tr>
<td>ZTVL</td>
<td>left engine thrust force in body z-direction (TV), lbs</td>
</tr>
<tr>
<td>ZTVR</td>
<td>right engine thrust force in body z-direction (TV), lbs</td>
</tr>
<tr>
<td>ZZABL</td>
<td>d/dt of left engine thrust in AB before rate limiting, lbs/sec</td>
</tr>
<tr>
<td>ZZABR</td>
<td>d/dt of right engine thrust in AB before rate limiting, lbs/sec</td>
</tr>
</tbody>
</table>

A.21
APPENDIX B - EXAMPLE CASES

Trim to Level Flight (TCASE=1)

The following wings level (TCASE=1) trim cases are demonstrated by an example terminal session:

1. \( M=0.6, H=10,000 \) (ft), flight path angle \( (\gamma) = 0 \).
2. \( M=0.8, H=10,000 \) (ft), flight path angle \( (\gamma) = 0 \).
3. \( \alpha = 5^\circ, H=10,000 \) (ft), flight path angle \( (\gamma) = 0 \).
4. \( \alpha = 10^\circ, H=10,000 \) (ft), flight path angle \( (\gamma) = 0 \).

Commands entered at the keyboard are in **bold courier**. The program and VMS responses are in **plain Courier**. Comments inserted after the session to explain actions are in *italics*.

AGCB9$: 8setup_bas
$ assign [CSB.FL8BAS.DATA_FILES]T5AERO.FL8BAS t5aero
$ assign [CSB.FL8BAS.DATA_FILES]T5ENG.FL8BAS t5eng
$ assign [CSB.FL8BAS.DATA_FILES]FL8BAS.DCT for029
$ set noverify
AGCB9$: type Fl8tr.dat

F18 with 60% fuel, tip missiles, level turn

------------------------------- MASS, INERTIAS, AND CG LOCATION

<table>
<thead>
<tr>
<th></th>
<th>WT (LBS)</th>
<th>WEIGHT</th>
</tr>
</thead>
<tbody>
<tr>
<td>33310.0</td>
<td></td>
<td></td>
</tr>
<tr>
<td>23000.0</td>
<td>IXX (SLUG*FT**2)</td>
<td>INERTIA ABOUT X AXIS</td>
</tr>
<tr>
<td>151293.0</td>
<td>IYY (SLUG*FT**2)</td>
<td>INERTIA ABOUT Y AXIS</td>
</tr>
<tr>
<td>169945.0</td>
<td>IZZ (SLUG*FT**2)</td>
<td>INERTIA ABOUT Z AXIS</td>
</tr>
<tr>
<td>-2971.0</td>
<td>IXZ (SLUG*FT**2)</td>
<td>XZ PLANE INERTIA PRODUCT</td>
</tr>
<tr>
<td>455.0</td>
<td>FSCG (IN)</td>
<td>CG LOC - FUSELAGE STATION</td>
</tr>
<tr>
<td>0.0</td>
<td>BLCG (IN)</td>
<td>CG LOC - BUTTOCK LINE</td>
</tr>
<tr>
<td>102.8</td>
<td>WLCG (IN)</td>
<td>CG LOC - WATER LINE</td>
</tr>
</tbody>
</table>

------------------------------- FLIGHT CONDITIONS AND MODELING OPTIONS

| F | LTHVEC | THRUST VECTORING ON |
| T | LFCS   | FLT CONTROL SYTEM ON |
| F | LTHDMS | USE DMS PLA SCHEDULE |
| T | LRTE   | USE R/T EQV AERO |
| 0.60000 | MACHTR | (N.D.) |
| 10000.00 | HIC | (FT) |
| 30.00 | MUDGTR | (DEG) |
| 1.00000 | GLOAD | (G) |

------------------------ TRIM SETUP IF LTR = .TRUE

1. TCASE | 1=LEVEL, 2=COORD TURN (MUDGTR), 3=PULL UP (GLOAD)
4. NUMBER OF DRIVER VARIABLES

<table>
<thead>
<tr>
<th>ELEMENT LIMITS</th>
<th>VARIABLE NAME, UNITS</th>
</tr>
</thead>
<tbody>
<tr>
<td>14 -2.500</td>
<td>5.000 PCSTR (INCHES )</td>
</tr>
<tr>
<td>16 31.000</td>
<td>127.000 DPSYTR (% POWER)</td>
</tr>
<tr>
<td>3 -0.100</td>
<td>1.500 ALFTR (KADIANS)</td>
</tr>
<tr>
<td>7 -1.500</td>
<td>1.500 THETR (RADIANS)</td>
</tr>
</tbody>
</table>

4. NUMBER OF DRIVEN VARIABLES

| ELEMENT VARIABLE NAME, UNITS |
|-----------------------------|----------------|
| 1 UD | (FT/SEC2) |

B.1
INITIAL CONDITIONS:

0.60000002 MACHTR (N.D.)
0.00000000E+00 BETTR (RADIANS)
0.43141015E-01 ALFTR (RADIANS)
0.00000000E+00 PIC (RAD/SEC)
0.00000000E+00 QIC (RAD/SEC)
0.00000000E+00 RIC (RAD/SEC)
0.43145921E-01 THETR (RADIANS)
0.00000000E+00 PHITR (RADIANS)
0.00000000E+00 PSITR (RADIANS)
0.00000000E+00 DTVL (DEGREES)
0.00000000E+00 DTVR (DEGREES)
0.00000000E+00 PCATR (INCHES)
0.23838108E-01 PCSTR (INCHES)
0.00000000E+00 PCRTR (LBS)
60.480717 DPSYTR (% POWER)
0.00000000E+00 DPASTR (% POWER)
0.35326593E-01 DSSYTR (DEGREES)
0.00000000E+00 DSASTR (DEGREES)
0.00000000E+00 DASYTR (DEGREES)
0.00000000E+00 DAASTR (DEGREES)
0.00000000E+00 DRSYTR (DEGREES)
3.2825463 DNSYTR (DEGREES)
0.00000000E+00 DNASTR (DEGREES)
3.4605167 DFSYTR (DEGREES)
0.00000000E+00 DFASTR (DEGREES)
0.00000000E+00 CSB (DEGREES)
30.000000 MUDGTR (DEGREES)
0.00000000E+00 future expansion

SEND OF DATA READING SECTION

CASE SELECTIONS:

TCASE  1 STRAIGHT & LEVEL STEADY STATE
       2 COORDINATED TURN STEADY STATE
       3 PULL-UP STEADY STATE

TRIM VALUE SELECTIONS:

TRIM DRIVER ARRAY                      TRIM OUTPUT ARRAY
1 MACHTR (N.D.)                         1 UD (FT/SEC2)
2 BETTR (RADIANS)                       2 VD (FT/SEC2)
3 ALFTR (RADIANS)                       3 WD (FT/SEC2)
4 PIC (RAD/SEC)                         4 PD (RAD/SEC2)
5 QIC (RAD/SEC)                         5 QD (RAD/SEC2)
6 RIC (RAD/SEC)                         6 RD (RAD/SEC2)
7 THETR (RADIANS)                       7 GAMZR (RADIANS)
8 PHITR (RADIANS)                       8 PHIZR (RADIANS)
9 PSITR (RADIANS)                       9 THE (RADIANS)
10 GAMTR (RADIANS)                      10 LAMDA (RADIANS)
11 DTVL (DEGREES)                       11 FYTOT (G S)
12 DTVR (DEGREES)                       12 CL-CLTR (N.D.)
Execute file 'fl8bas.exe'.

The ACSL Licence will terminate in 3 months.
Ask your systems manager to contact Mitchell and Gauthier for new key.
Telephone (USA) 508/369-5115

Switching CMD unit to 4 to read FL8BAS.CMD

Start case (1). TSTOP=0.0 so program stops immediately after trim attempt. LTR true causes trim attempt to be made.

>>> READING VALUES TO INIT TRIM SEARCH (F18TR FILE)
>>> READING AERO DATA
TIME ELAPSED = 7.238281 SECONDS

>>> READING ENGINE DATA
TIME ELAPSED = 1.339844 SECONDS

NORM OF Y ON FIRST PASS = 3.0825590E-03
COLUMN 2 NOT REPEATABLE. ERROR = 6.519258022308350E-009
TRIM ACHIEVED. ERROR = 4.4315234E-06
ITERATIONS REQUIRED = 27
t exceeds tstop

Set display column width=80 (required only for this demo).

Display selected XTRIM variables.

Change desired Mach for new trim.
Start case (2)
ACSL> d    machtr, hic, vt, ud, vd, pd, qd, rd, thedg, alfdg, ...
ACSL> pcstr, dpsytr
MACHTR 0.80000000        HIC 10000.0000        VT 861.923000
UD-2.7995E-04             VD 0.             WD 5.5112E-04
PD 0.                    QD 3.8318E-05       RD 0.
THEDG 1.32924000         ALFDG 1.32953000     PCSTR 1.00055000
DPSYTR 80.50410000

ACSL> s    ixsel=14,16,1,7

Change XTRIM select list by replacing ALFTR with MACHTR. This causes MACHTR to be varied while ALFTR is left fixed. Useful for trimming to a desired angle of attack.
Set ALFTR in radians to produce 5 degrees α.
Start case (3)

ACSL> s    alft=.087266462

ACSL> start
NORM OF Y ON FIRST PASS = 1.022277
COLUMN 2 NOT REPEATABLE. ERROR = 4.9511334054841E-07
COLUMN 4 NOT REPEATABLE. ERROR = 2.402740051365981E-07
TRIM ACHIEVED. ERROR = 2.0998859E-06
ITERATIONS REQUIRED = 16
t exceeds tsta

ACSL> d    machtr, hic, vt, ud, vd, pd, qd, rd, thedg, alfdg, ...
ACSL> pcstr, dpsytr, phi
MACHTR 0.42064100        HIC 10000.0000        VT 453.200000
UD-3.4658E-05             VD 0.             WD 7.4657E-06
PD 0.                    QD 7.1250E-06       RD 0.
THEDG 5.00025000         ALFDG 5.00000000     PCSTR 0.21334900
DPSYTR 55.06370000       PHI 0.

ACSL> s    alft=.1745329

Set ALFTR in radians to produce 10 degrees α.
Start case (4)

ACSL> start
NORM OF Y ON FIRST PASS = 0.2984953
TRIM ACHIEVED. ERROR = 2.2749262E-05
ITERATIONS REQUIRED = 11
t exceeds tsta

ACSL> d    machtr, hic, vt, ud, vd, pd, qd, rd, thedg, alfdg, ...
ACSL> pcstr, dpsytr, phi
MACHTR 0.29906200        HIC 10000.0000        VT 322.210000
UD-5.2243E-04             VD 0.             WD 8.9943E-04
PD 0.                    QD 8.4760E-05       RD 0.
THEDG 10.00040000        ALFDG 10.00000000     PCSTR 0.50991900
DPSYTR 60.91970000       PHI 0.

ACSL> stop
End ACSL run
AGCB9$
Trim to Bank Angle (TCASE=2)

The following trim to bank angle (TCASE=1) trim cases are demonstrated by an example terminal session. The session is begun by reading in the TCASE=1 trim data file f18tr.dat, then using run time commands to set up the bank angle trim.

(1) \(M=0.6, H=10,000 \text{ (ft), wings level, TCASE}=1\)
(2) \(M=0.6, H=10,000 \text{ (ft), TCASE}=2, \text{ Bank angle } (\mu) = 30'\)
(3) \(M=0.6, H=10,000 \text{ (ft), TCASE}=2, \text{ Bank angle } (\mu) = 60'\)

AGCB9$ acsl/run f18bas

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Ask your systems manager to contact Mitchell and Gauthier for new key
Telephone (USA) 508/369-5115

Switching CMD unit to 4 to read F18BAS.CMD
ACSL>start
Start case (1)
>>> READING VALUES TO INIT TRIM SEARCH (F18TR FILE)
>>> READING AERO DATA
TIME ELAPSED = 7.230469 SECONDS
>>> READING ENGINE DATA
TIME ELAPSED = 1.339844 SECONDS
NORM OF Y ON FIRST PASS = 3.0825590E-03
COLUMN 2 NOT REPEATABLE. ERROR = 6.519258022308350E-009
TRIM ACHIEVED. ERROR = 4.4315234E-06
ITERATIONS REQUIRED = 27
t exceeds tstp
ACSL>s tcwprn=80
ACSL>d machtr,hic,tcase,alfdg,thedg,pcstr,dpsytr
MACHTR 0.60000000 HIC 10000.0000 TCASE 1
ALFDG 2.47177000 THEDG 2.47138000 PCSTR-0.06876620
DPSYTR 60.47870000
ACSL>d ud,vd,wd,pd,qd,rd
UD 2.3931E-04 VD 0. WD 1.3487E-04
PD 0. QD-1.3995E-05 RD 0.
ACSL>s tcase=2,11imdf=.t-, nxtr=8
Convert from wings level to a trim at bank angle using the TCASE=2 option. Expand trim from 4x4 to 8x8. NYTR will be automatically set to NXTR.

ACSL>s ixsel=15,13,2,8,7,3,14,16
ACSL>s iysel=6,4,2,11,1,3,5,7
ACSL>s mudgtr=30
ACSL>start
Choose desired bank angle.
Start case (2)
NORM OF Y ON FIRST PASS = 7.2131425E-02
MUMAX REACHED. CALCULATE NEW SENSITIVITY MATRIX.
NORM OF Y ON FIRST PASS = 3.7534295E-02
TRIM ACHIEVED. ERROR = 2.8616143E-05
ITERATIONS REQUIRED = 46
t exceeds tstp
ACSL>d machtr,hic,phidg,mudgtr,az,alfdg,thedg,phidg,dpsytr
MACHTR 0.60000000 HIC 10000.0000 PHIDG 30.02990000
MUDGTR 30.00000000 AZ-1.15330000 ALFDG 2.81582000
THEDG 2.42915000 PHIDG 30.02990000 DPSYTR 61.21180000
ACSL>d ud,vd,wd,pd,qd,rd
UD 2.3536E-06 VD 6.9801E-05 WD-1.3113E-05
PD-2.2889E-04 QD-1.9547E-06 RD 1.6206E-06
ACSL> s mudgtr=60
ACSL> start
Start case (3)
NORM OF Y ON FIRST PASS = 0.1437438
COLUMN 8 NOT REPEATABLE. ERROR = 1.303851604461670E-008
TRIM ACHIEVED. ERROR = 1.1091912E-05
ITERATIONS REQUIRED = 26
\[ t \text{ exceeds } \text{tstp} \]
ACSL> d machtr,hic,phidg,mudgtr,az,alfdg,thedg,phidg,dpsytr
\[ \text{MACHTR 0.60000000} \]
\[ \text{HIC 10000.0000} \]
\[ \text{PHIDG 60.08110000} \]
\[ \text{MUDGTR 60.00000000} \]
\[ \text{AZ-1.99337000} \]
\[ \text{ALFDG 4.67035000} \]
\[ \text{THEDG 2.30884000} \]
\[ \text{PHIDG 60.08110000} \]
\[ \text{DPSYTR 76.63980000} \]
2 g's of normal load (stability frame) are produced by 60° of bank angle. AZ is in the body frame and is slightly different from NZ in the stability frame.
ACSL> s lwtr=.t.
ACSL> start
NORM OF Y ON FIRST PASS = 1.1091912E-05
ALREADY TRIMMED.
\[ t \text{ exceeds tstp} \]
ACSL> stop
End ACSL run

End session
Steady State Pull-Up (TCASE=3)

The following steady-state pull-up (TCASE=3) trim cases are demonstrated by an example terminal session. The session is begun by reading in the TCASE=1 trim data file flstr.dat, then using run time commands to set up the pull-up trim.

(1) M=0.6, H=10,000 (ft), wings level, TCASE=1, flight path angle (\(\gamma\)) = 0.
(2) M=0.6, H=10,000 (ft), TCASE=3, GLOAD \((n_2)\) = 2 g’s.
(3) M=0.6, H=10,000 (ft), TCASE=3, GLOAD \((n_2)\) = 4 g’s.

AGCB9$ copy fl8tr_tcl.dat fl8tr.dat Copy fl8tr.dat file used for TCASE=1 trim cases into generic file read by fl8bas simulation.

AGCB9$ acsl/run fl8bas

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Switching CMD unit to 4 to read F18BAS.CMD

ACSL> start
Start case (1)

>>> READING VALUES TO INIT TRIM SEARCH (F18TR FILE)

>>> READING AERO DATA
TIME ELAPSED = 7.351563 SECONDS

>>> READING ENGINE DATA
TIME ELAPSED = 1.492188 SECONDS

NORM OF Y ON FIRST PASS = 3.0825590E-03
COLUMN 2 NOT REPEATABLE. ERROR = 6.519258022308350E-009
TRIM ACHIEVED. ERROR = 4.4315234E-06
ITERATIONS REQUIRED = 27
t exceeds tstp

ACSL> t cwpnr=80

ACSL> d tcase, alfdg, thedg, machtr, hic
TCASE 1 ALFDG 2.47177000 THEDG 2.47138000
MACHTR 0.60000000 HIC 10000.0000

Selected XTRIM variables
IXSEL 16
7
0
0

ACSL> d iysel
IYSEL 3
5
0
0

ACSL> d az
AZ-0.99906600

ACSL> s tcase=3, gload=2

TCASe=3 sets pitch rate automatically for a pull-up with load (g’s) = GLOAD.
Start case (2)

ACSL> start
NORM OF Y ON FIRST PASS = 0.2461748
COLUMN 2 NOT REPEATABLE. ERROR = 1.22028140412340E-007
TRIM ACHIEVED. ERROR = 7.6116430E-06
ITERATIONS REQUIRED = 10
t exceeds tstp

ACSL> d tcase, alfdg, thedg, machtr, hic, az
TCASE 3 ALFDG 4.67142000 THEDG 4.67179000
MACHTR 0.60000000 HIC 10000.0000
AZ-1.99336000
ACSL> d ud, wd, qd
    UD 5.5424E-04       WD-2.6588E-04       QD-2.2835E-05
ACSL> s gload=4
ACSL> start
Start case (3)
NORM OF Y ON FIRST PASS = 0.4928297
COLUMN 3 NOT REPEATABLE. ERROR = 3.63249280303268E-007
TRIM ACHIEVED. ERROR = 5.9509330E-07
ITERATIONS REQUIRED = 20
t exceeds tstp
ACSL> d dpsytr, q
Show required throttle (%) and pitch rate (r/s).
    DPSYTR 112.504000       Q 0.14931300
ACSL> d tcase, alfdg, thedg, machtr, hic, az
    TCASE 3       ALFDG 8.99947000       THEDG 8.99940000
    MACHTR 0.60000000       HIC 10000.0000       AZ-3.95076000
ACSL> stop
End ACSL run
The mathematical model and associated computer program to simulate a twin-tailed high performance fighter airplane (McDonnell Douglas F/A-18) are described. The simulation program is written in the Advanced Continuous Simulation Language language. The simulation math model includes the non-linear, six degree-of-freedom rigid-body equations, an engine model, sensors, and first order actuators with rate and position limiting. A simplified form of the F/A-18 digital control laws (version 8.3.3) are implemented. The simulated control law includes only inner loop augmentation in the up and away flight mode. The aerodynamic forces and moments are calculated from a wind-tunnel-derived database using table look-ups with linear interpolation. The aerodynamic database has an angle-of-attack range of -10° to +90° and a sideslip range of -20° to +20°. The effects of elastic deformation are incorporated in a quasi-static-elastic manner. Elastic degrees of freedom are not actively simulated. In the engine model, the throttle-commanded steady-state thrust level and the dynamic response characteristics of the engine are based on airflow rate as determined from a table look-up. Afterburner dynamics are switched in at a threshold based on the engine airflow and commanded thrust.