The item to be cleared is a low-fidelity software simulation model of a hypothetical free-flying robot designed for use in zero gravity environments.

This simulation model works with the HCC simulation system that was developed by Xerox PARC and NASA Ames Research Center. HCC has been previously cleared for distribution.

When used with the HCC software, the model computes the location and orientation of the simulated robot over time. Failures (such as a broken motor) can be injected into the simulation to produce simulated behavior corresponding to the failure.

Release of this simulation will allow researchers to test their software diagnosis systems by attempting to diagnose the simulated failure from the simulated behavior.

This model does not contain any encryption software nor can it perform any control tasks that might be export controlled.
This file is the HCC code for the PSA simulation. PSA was officially renamed to SMR, but the name PSA has stuck for the project. Both names are used for the project, and both might be around in code below. */

#define "mathlib"

#ifdef EXTERNAL_CONTROLLER
#module "psa_controller_sdoof"
#max_step 0.01
#endif

/* define constants used in code below */
#define m 5  // mass of the PSA kg
#define rad 0.1 // radius of the PSA m

/* define constants used to control behavior of HCC */
/* see HCC programmer's manual for explanation of these */
#define MEMORY_MAX 8000000
#define EPSILON 1.0e-11
#define INTEGRATION_INIT 0.0001
#define SAMPLE_INTERVAL_MIN 0.01
#define SAMPLE_INTERVAL_MAX 0.01  // Good number = 0.01

class CFan {

    /* Description of variables:
       k1       Curvefit constant for thrust of fan as
                function of fan speed
       k2       Curvefit for modeling aerodynamic torque
                on motor as function of fan speed
       inertia  Rotational inertia of fan along spin axis
       tm       Torque constant of motor
                (torque = tm * current)
       vel      Angular velocity of fan (rad/s)
       current  Current sent to motor by controller
       force    Thrust on PSA due to fan
       moment   Total torque provided by motor
       aero_torque  Torque of fan used to provide thrust,
                     overcome drag, overcome friction, etc.
       h        Angular momentum of fan */

    public interval vel, force, moment, aero_torque, h;

    public CFan(interval i, interval k1, interval k2, interval inertia,
                 interval tm, interval current) {
        vel = 0.0;

        always {
            /* Fan model with fan dynamics. k1 and k2 are two constants
               determined empirically and passed in to the object.
               This model has the torque created by the fan motor being
x = x_init; y = y_init; z = z_init;
qu1 = q1_init; q2 = q2_init; q3 = q3_init; q4 = q4_init;
u = 0; v = 0; w = 0; p = 0; q = 0; r = 0;
always {

/* Calculate total moment in each component direction */
l_moment:=(F5.force-F4.force)*radius - F2.aero_torque - F3.aero_torque;
m_moment:=(F1.force-F0.force)*radius - F4.aero_torque - F5.aero_torque;
n_moment:=(F3.force-F2.force)*radius - F0.aero_torque - F1.aero_torque;

/* Balance of moments in each component direction, used to find angular velocities (p, q, r). */
p' := (l_moment - F2.h' - F3.h' + F4.h*r + F5.h*r - F0.h*q - F1.h*q) / mom_of_in;
q' := (m_moment - F4.h' - F5.h' - F2.h*r - F3.h*r + F0.h*p + F1.h*p) / mom_of_in;
r' := (n_moment - F0.h' - F1.h' + F2.h*q + F3.h*q - F4.h*p - F5.h*p) / mom_of_in;

/* Calculate orientation based on (p, q, r). Orientation is in quaternion form. */
q1' := (q4*p - q3*q + q2*r)/2;
q2' := (q3*p + q4*q - q1*r)/2;
q3' := (-q2*p + q1*q + q4*r)/2;
q4' := (-q1*p - q2*q - q3*r)/2;

/* Calculate total force in each component direction */
x_force := F2.force + F3.force;
y_force := F4.force + F5.force;
z_force := F0.force + F1.force;

/* Balance of forces in each component direction, used to find (u, v, w). Note the coriolis forces added as a result of the body-fixed coordinate system used in the force balance. */
u' := (x_force)/mass - 2*(q*w - r*v);
v' := (y_force)/mass - 2*(r*u - p*w);
w' := (z_force)/mass - 2*(p*v - q*u);

/* Convert the body-fixed velocities to global velocities and integrate to find global position (x, y, z) */
x' := u*(1 - 2*q3^2 - 2*q1^2) + v^2*(q1*q2 - q3*q4) + w^2*(q3*q1 + q2*q4);
y' := u^2*(q1^2 + q4^2) + v^2*(1 - 2*q1^2 - 2*q3^2) + w^2*(q2*q3 - q1*q4);
z' := u^2*(q3*q1 - q2*q4) + v^2*(q2*q3 + q1*q4) + w^2*(1 - 2*q1^2 - 2*q2^2);

#endif EXTERNAL_CONTROLLER
    junk = update_state(time, u, v, w, p, q, r, u', v', w', p', q', r');
#endif
} // end always

sample(x, y, z, u, v, w, x', y', z', u', v', w', q1, q2, q3, q4, p, q, r);

} // end CDynamics constructor
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// Apply a conversion factor to calculate the motor current for each fan, based on the desired thrust of the fan. This current is then sent to the fan of the PSA. */
fan0current = 8.19 * fan0force; //3.631
fan1current = 8.19 * fan1force;
fan2current = 8.19 * fan2force;
fan3current = 8.19 * fan3force;
fan4current = 8.19 * fan4force;
fan5current = 8.19 * fan5force;
} // end always

} //end CController constructor

} // end CController class def.

/******************************************************************************
CPlanner class definition
*******************************************************************************/
/* The PlannerClass is used to send the desired velocities to the ControllerClass. Right now, this is a lookup table based on the simulation time. It could come from a more advanced path planner as well.

Note that these are desired velocities, even though the variable names are just x, y, etc. */

class CPlanner {
  public interval xdes, ydes, zdes;
  public interval roll_des, pitch_des, yaw_des;
  public CPlanner() {
    always {
      /* Set all values to 0 as the default, for all times where they are not defined in the list below. */
      /* I had a problem with this working - after 43 seconds, these values end up being undefined. HCC won't crash, but the fan's force values become undefined, and the PSA will coast in the last direction it is facing. */
      unless ( (time >= 0) | | (time <= 43) ) {
        xdes = 0.0; ydes = 0.0; zdes = 0.0;
        roll_des = 0.0; pitch_des = 0.0; yaw_des = 0.0;
      }
      if ( (time >= 0.0) & & (time < 1.0) ) {
        xdes = 0.0; ydes = 0.0; zdes = 0.0;
        roll_des = 0.0; pitch_des = 0.0; yaw_des = 0.1;
      }
      /* Send PSA forward */
    }
  }
}
```
#ifdef EXTERNAL_CONTROLLER
interval junk = init_external_controller();
#endif

/****************************
Section to change depending on if using visualization
****************************/

#ifndef VISUALIZATION
/*Global variable */
CPSA psa0;
psa0 = new CPSA(0, 0, 0, 0, 0, 0, 1);
#endif