Documentation

PDB LS-DYNA

WorldSID 50th – Version 7.1



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1. General information

The development and validation has been performed on different platforms. The following LS-DYNA versions have been used:

LS-DYNA Version	Date	Revision Nr.
971 R7.1.3 MPP	05/19/2016	114888 Product ID 114888
971 R9.3 MPP	07/09/2018	129523 Product ID 129523
971 R9.3 MPP	07/09/2018	143600 Product ID 143600

Table 1: LS-DYNA versions

To offer a variety of LS-DYNA versions for the user to run the current WorldSID model, we tested the following releases with the barrier sled tests:

LS-DYNA Version	Date	Revision Nr.	recommended
971 R7.1.3 MPP	05/19/2016	114888 Product ID 114888	yes
971 R9.3 MPP	07/09/2018	129523 Product ID 129523	yes
971 R9.3 MPP	07/09/2018	143600 Product ID 143600	yes

 Table 2: recommended LS-DYNA versions

With the version 7.1 of the WorldSID 50^{th} model the following keyword files are delivered:

File name	Content
worldSID50_pdb_v7.1_mm_ms_kg.key	Dummy model; the file name might vary depending on the system of units
worldSID50_pdb_v7.1_mm_ms_kg_IR- TRACC_left_v1.0.key	IR-TRACC LHD include file; the file name might vary depending on the system of units
worldSID50_pdb_v7.1_mm_ms_kg_IR- TRACC_right_v1.0.key	IR-TRACC RHD include file; the file name might vary depending on the system of units
worldSID50_pdb_v7.1_Ballast_left_v1. 0.key	Ballast LHD include file
worldSID50_pdb_v7.1_Ballast_right_v1 .0.key	Ballast RHD include file
worldSID50_pdb_v7.1_arm_sleeve_ v2.0.key	Arm_sleeve model for ENCAP Far-Side
Psg_v2.1	Script to generate pre-simulation input (chapter 3.2).
wsid50_v7.1_all_units_server.asc	License file; the file can be used in different system of units



wsid50_v7.1_all_units_load_curves_ work.key	Work file used for pre-processing instead of license file. The file name might vary depending on the system of units
worldSID50_pdb_v7.1_H-Point_tool.key	H-Point measurement device
worldSID50_pdb_v7.1.X_mm_ms_kg_R ibEye_left_v4.0.key	RibEye LHD model; the file name might vary depending on the system of units
worldSID50_pdb_v7.1.X_mm_ms_kg_R ibEye_right_v4.0.key	RibEye RHD model; the file name might vary depending on the system of units

 Table 3: Delivered Files

The work file wsid50_pdb_vx.x_all_units_load_curves_work.key can be used for pre-processing the dummy.

This work file includes the same input as the encrypted license file. The only difference is the scaling of the load curves in the work file. The load curves are scaled randomly in a wrong range and they are much too soft to be used for a LS_DYNA simulation. But the file can be used to observe the quality and course of the material curves.

A LS-DYNA simulation in use of the work file will give wrong results and is very unstable.

The numbering scheme of the original model is shown in Table 4. On request, we deliver renumbered input decks, according to user specifications.

Component	Min ID	Max ID	Total number
Nodes	10000	668195	596916
Solids	11001	486467	465074
Beams	10000	480054	1138
Shells	160001	347463	301176
Element Mass	10001	10002	2
Discrete elements	10036	10365	68
Accelerometer	1001	1023	22
Set node	1001	21539	6502
Set shell	1029	1029	1
Set parts	1001	1582	64
Parts	1	991	947
Materials	1001	1099	82
Sections	1003	1195	70
Hourglass	1001	1010	6
Airbags	1	2	2
Airbag reference geometry	1	2	2
Joints	1024	1109	37
Joint stiffness	1001	1184	153
Nodal rigid bodies	10024	21539	6480
Contacts	1001	1069	26
Local coordinate systems	1001	1380	221



Load curves / tables	1001	1150	129
Define SD orientation	1001	1120	32
Time history nodes	10001	612017	93
Time history beam elements	10000	10256	22
Time history discrete elements	10040	10365	56

Table 4: Model numbering scheme



1.1 Keywords used

The following control and database keywords are used:

*CONTROL_ACCURACY	*CONTROL_SHELL
*CONTROL_BULK_VISCOSITY	*CONTROL_SOLID
*CONTROL_CONTACT	*CONTROL_SOLUTION
*CONTROL_MPP_IO_NODUMP	*CONTROL_TERMINATION
*CONTROL_MPP_DECOMPOSITION	*CONTROL_TIMESTEP
_ARRANGE_PARTS	
*CONTROL_ENERGY	*CONTROL_HOURGLASS
*CONTROL_OUTPUT	

Table 5: Control cards used

The following database cards are defined:

*DATABASE_ABSTAT	*DATABASE_HISTORY_NODE_ID
*DATABASE_BINARY_D3PLOT	*DATABASE_HISTORY_NODE_LOCAL_
	ID
*DATABASE_BINARY_RUNRSF	*DATABASE_JNTFORC
*DATABASE_DEFORC	*DATABASE_MATSUM
*DATABASE_ELOUT	*DATABASE_NODOUT
*DATABASE_EXTENT_BINARY	*DATABASE_RBDOUT
*DATABASE_GLSTAT	*DATABASE_RCFORC
*DATABASE_HISTORY_BEAM_ID	*DATABASE_SBTOUT
*DATABASE_HISTORY_DISCRETE_ID	*DATABASE_SLEOUT

Table 6: Database cards used

The following material models are used:

*MAT_ELASTIC	*MAT_RIGID
*MAT_FU_CHANG_FOAM	*MAT_RIGID_DISCRETE
*MAT_FABRIC	*MAT_SHAPE_MEMORY
*MAT_LINEAR_ELASTIC_DISCRETE_B	*MAT_SIMPLIFIED_RUBBER
EAM	*MAT_SIMPLIFIED_RUBBER
*MAT_NONLINEAR_ELASTIC_DISCRE	_WITH_DAMAGE
TE_BEAM	*MAT_SPRING_ELASTIC
*MAT_NULL	*MAT_SPRING_NONLINEAR_ELASTIC
*MAT_PLASTIC_KINEMATIC	*MAT_VISCOELASTIC

Table 7: Material models used

The following other keywords are used:

*AIRBAG_HYBRID	*ELEMENT_SOLID
*AIRBAG_REFERENCE_GEOMETRY_RDT	*END
*CONSTRAINED_EXTRA_NODES_SET	*HOURGLASS
*CONSTRAINED_JOINT_SPHERICAL_ID	*INCLUDE



	F
*CONSTRAINED_JOINT_STIFFNESS_	*INITIAL_FOAM_REFERENCE_
GENERALIZED	GEOMETRY
*CONSTRAINED_JOINT_STIFFNESS_	*KEYWORD
TRANSLATIONAL	
*CONSTRAINED_NODAL_RIGID_BODY	*NODE
*CONSTRAINED_RIGID_BODIES	*PART
*CONTACT_AUTOMATIC_SINGLE_SURFACE	*PARAMETER
*CONTACT_FORCE_TRANSDUCER_PENALTY	*PARAMETER_EXPRESSION
*CONTACT_TIED_SHELL_EDGE_TO_	*SECTION_BEAM
SURFACE	
*DAMPING_PART_STIFFNESS	*SECTION_DISCRETE
*DEFINE_COORDINATE_NODES	*SECTION_SHELL
*DEFINE_CURVE	*SECTION_SOLID
*DEFINE_SD_ORIENTATION_TITLE	*SET_NODE_LIST
*DEFINE_TABLE	*SET_PART_LIST
*ELEMENT_BEAM	*SET_PART_COLLECT
*ELEMENT_DISCRETE	*SET_SHELL_LIST
*ELEMENT_SEATBELT_	*TITLE
ACCELEROMETER	
*ELEMENT_SHELL	*ELEMENT_MASS_NODE_SET

Table 8: Other keywords used in the model

After the *END keyword the following Primer keywords are defined:

*ASSEMBLY	*MECHANISM_START
*CONNECTION_HINGE	*MECHANISM END
*CONNECTION_LINE	*POINT_LOCATION
*DUMMY_END	*POSITION
*DUMMY_START	*UNITS
*H_POINT	

Table 9: Primer keywords used



1.2 Mass Measurements

The follow table shows current mass measurements between ISO specification masses (2013) und WSID 50^{th} Model version 7.1:

Item	Hardware	Hardware	ISO F	Range	Model
	Mass (KG)	+/- (KG)			Mass (KG)
Head	4.22	0.05	4.17	4.27	4.21
Neck	2.84	0.15	2.69	2.99	2.86
Upper Torso	20.55	1.00	19.55	21.55	20.93
Lower Torso	17.77	0.90	16.87	18.67	17.04
Arm Left	1.77	0.09	1.68	1.86	1.82
Arm Right	1.77	0.09	1.68	1.86	1.82
Upper Leg, Left	6.71	0.30	6.41	7.01	6.61
Lower Leg, Left	5.09	0.13	4.96	5.22	5.01
Upper Leg, Right	6.71	0.30	6.41	7.01	6.61
Lower Leg, Right	5.09	0.13	4.96	5.22	5.01
Clothing, with Sleeves	1.85	0.09	1.76	1.94	1.70
Total	74.35	3.74	70.61	78.09	73.62

 Table 10: Mass measurements between hardware and model



2. Extraction of occupant injury criteria

To extract occupant injury criteria from the model, the following preparations have been made.

2.1 Sign convention in the Model

All relevant coordinate systems are defined according to the SAEJ211 norm. This means that all coordinate axes in the dummy are oriented with respect to an upright standing dummy. Thus the x-axis of the coordinate systems in the upper legs points upwards as shown in Figure 1.



Figure 1: Orientation of the coordinate systems for accelerometers and load cells in the WORLDSID 50th model

Only the coordinate systems for evaluating injury criteria are oriented in this scheme. There are many more coordinate systems in the model which are sometimes oriented arbitrarily because of internal features in the dummy.



2.2 Accelerations

2.2.1 Head acceleration



Figure 2: Head accelerometer and local coordinate directions

There are two nodes from the marked point for the head acceleration. An accelerometer is defined at the first node. The second node is for global acceleration. The first prints the results in the NODOUT file in the local coordinate system shown in Figure 2.

Item	Node-ID	Label	Available components
Head	10001	HEAD0000WSAC	local x-,y-,z- acceleration
Head global	10123	HEAD00GBWSAC	global x-,y-,z- acceleration

Table 11: Head accelerometer nodes

2.2.2 T1, T4 and T12 acceleration



Figure 3: T1, T4 and T12 accelerometer nodes



The Figure 3 depicts the points, each point has two nodes which are used as output nodes in the NODOUT file for T1, T4 and T12 acceleration. For each first node, an accelerometer with the local directions is defined as shown in the Figure. For each second node is for global acceleration.

Item	Node-ID	Label	Available components
T1	10002	THSP0100WSAC	local x-,y-,z- acceleration
T1 global	10139	THSP01GBWSAC	global x-,y-,z- acceleration
T4	10003	THSP0400WSAC	local x-,y-,z- acceleration
T4 global	10140	THSP04GBWSAC	global x-,y-,z- acceleration
T12	10004	THSP1200WSAC	local x-,y-,z- acceleration
T12 global	10141	THSP12GBWSAC	global x-,y-,z- acceleration

Table 12: T1, T4 and T12 accelerometer nodes

2.2.3 Pelvis acceleration



Figure 4: Node to extract pelvis acceleration.

In Figure 4, a plate cut through the pelvis along the z-x-plane is shown. The pelvis accelerometer is located at the back of the sacrum block. The results of the node 10005 are printed in the NODOUT file in the local coordinate system which is shown in Figure 4. The node 10142 is for global acceleration.

Item	Node-ID	Label	Available components
Pelvis	10005	PELV0000WSAC	local x-,y-,z- acceleration
Pelvis global	10142	PELV00GBWSAC	global x-,y-,z- acceleration

Table 13: Pelvis accelerometer nodes



2.2.4 Rib accelerations

The WorldSID 50th model is equipped with twelve rib accelerometers. On each single rib, one accelerometer is mounted on the impact side and one on the opposite side.



Figure 5: Cut through upper torso and position of rib accelerometer nodes

The nodal results are printed in the NODOUT file in the local coordinate systems of the accelerometers. On the impact side (left hand side for the left handed driver model) the nodes are:

Item	Node-ID	Label	Available components
shoulder rib	10010	SHRILE00WSAC	local x-,y-,z- acceleration
1. thorax rib	10011	TRRILE01WSAC	local x-,y-,z- acceleration
2. thorax rib	10012	TRRILE02WSAC	local x-,y-,z- acceleration
3. thorax rib	10013	TRRILE03WSAC	local x-,y-,z- acceleration
1. abdomen rib	10014	ABRILE01WSAC	local x-,y-,z- acceleration
2. abdomen rib	10015	ABRILE02WSAC	local x-,y-,z- acceleration

Table 14: Rib accelerometer nodes on the side of impact

On the reverse side of impact (right hand side for the left handed driver model) the accelerometer nodes are:



Item	Node-ID	Label	Available components
shoulder rib	10020	SHRIRI00WSAC	local x-,y-,z- acceleration
1. thorax rib	10021	THRIRI01WSAC	local x-,y-,z- acceleration
2. thorax rib	10022	THRIRI02WSAC	local x-,y-,z- acceleration
thorax rib	10023	THRIRI03WSAC	local x-,y-,z- acceleration
1. abdomen rib	10024	ABRIRI01WSAC	local x-,y-,z- acceleration
2. abdomen rib	10025	ABRIRI02WSAC	local x-,y-,z- acceleration

 Table 15:
 Rib accelerometer nodes on the side of impact

2.2.5 Marker evaluation

From WorldSID 50th v5.0, the model provide evaluation of marker. The Figure 6 depicts the nodes which are used as output nodes in the NODOUT file for marker in global system.







The nodes' list is:

Item	Node-ID	Label	Available components
marker sleeve-shoulder left	10048	SLEELEMAWSAC	global node output
marker sleeve-shoulder right	10049	SLEERIMAWSAC	global node output
marker head left	10050	HEADLEMAWSAC	global node output
marker head right	10051	HEADRIMAWSAC	global node output
marker arm-shoulder left	10052	SHLDLEMAWSAC	global node output
marker arm-shoulder right	10053	SHLDRIMAWSAC	global node output
marker arm end left	10054	ARMOLEMAWSAC	global node output
marker arm end right	10055	ARMORIMAWSAC	global node output
marker H-point left	10056	PELVLEMAWSAC	global node output
marker H-point right	10057	PELVRIMAWSAC	global node output
marker outer knee left	10058	KNEELEMOWSAC	global node output
marker outer knee right	10059	KNEERIMOWSAC	global node output
marker inner knee left	10060	KNEELEMIWSAC	global node output
marker inner knee right	10061	KNEERIMIWSAC	global node output
marker outer ankle left	10062	ANKLLEMOWSAC	global node output
marker outer ankle right	10063	ANKLRIMOWSAC	global node output
marker inner ankle left	10064	ANKLLEMIWSAC	global node output
marker inner ankle	10065	ANKLRIMIWSAC	global node output
right			

Table 16: Marker evaluation nodes list



2.3 Load cells

All load cells in the model are defined in the same way beside spherical joint hip global force. They are modeled using a discrete beam in combination with a local coordinate system. The results of the discrete beam are printed in the ELOUT file with respect to the local coordinate system. The local axes to evaluate the results of the beam are listed in Table 17.

Item	Component in elout file
local x-force	axial
local y-force	shear-s
local z-force	shear-t
local x-moment	torsion
local y-moment	moment-s
local z-moment	moment-t

Table	17.	Components	of FL		file	for	evaluating	load	cell	results
Iavie	1 /.	Components		001	me	101	evaluating	iuau	Cell	results

2.3.1 Upper and lower neck load cell



Figure 7: Upper and lower neck load cells

Item	Beam- ID	Label	Channels in physical dummy
Upper neck load cell	10000	NECKUP00WS	six-channel load cell
Lower neck load cell	10001	NECKLO00WS	six-channel load cell

Table 18: Upper and lower neck load cell beams

The neck load cells are six-channel load cells. This means that the forces and the moments in each direction of axis can be evaluated in the hardware.



2.3.2 Shoulder load cell left and right



Figure 8: Shoulder load cells, left and right.

Item	Beam-ID	Label	Channels in physical dummy
Left shoulder load cell	10002	SHLDLE00WS	three-channel load cell
Right shoulder load cell	10003	SHLDRI00WS	three-channel load cell

Table 19: Shoulder load cell beams, left and right hand side

The shoulder load cells are three-channel load cells. This means that the forces in each direction of axis can be evaluated in the hardware.



2.3.3 Lumbar load cell



Figure 9: Lumbar load cell in Sacrum block

The lumbar load cell is adapted into the sacrum block. The load cell is connected to the adapter plate and the lumbar spine is connected on this adapter plate.

Item	Beam-ID	Label	Channels in physical dummy
Lumbar load cell	10004	LUSP0000WS	six-channel load cell

Table 20: Lumbar load cell beam

The lumbar load cell is a six-channel load cell. This means that the forces and the moments in each direction of axis can be evaluated in the hardware.

2.3.4 Sacro-iliac load cells

The Sacro-iliac load cells are positioned on the left and right hand side of the sacrum block. They are used to measure the forces and moments which come from the pelvis bones into the sacrum block. The load cells are shown in the figure.





Figure 10: Sacro-iliac load cells, left and right hand side

Item	Beam-ID	Label	Channels in physical dummy
Sacro-iliac load cell left hand side	10005	SACRLE00WS	six-channel load cell
Sacro-iliac load cell right hand side	10006	SACRRI00WS	six-channel load cell

Table 21: Sacro-iliac load cell beams

The sacro-iliac load cells are six-channel load cells. This means that the forces and the moments in each direction of axis can be evaluated in the hardware.

2.3.5 Pubic symphysis load cell

Item	Beam-ID	Label	Channels in physical dummy
Pubic symphysis	10007	PUBC0000WS	one-channel load cell
load cell			

Table 22: Pubic symphysis load cell beam

The pubic load cell is a one-channel load cell. This means that only the force in the local y-direction can be evaluated in the hardware.





Figure 11: Pubic load cell adapted to pelvis bones

2.3.6 Femoral load cells

The upper legs of the WorldSID are equipped with four load cells: at the femoral neck of the left and right hand side, and in the middle of the left and right hand side femur.

Item	Beam-ID	Label	Channels in physical dummy
Femoral neck load cell left hand side	10008	FEACLE00WS	three-channel load cell
Femoral neck load cell right hand side	10009	FEACRI00WS	three-channel load cell
Femur load cell left hand side	10010	FEMRLE00WS	six-channel load cell
Femur load cell right hand side	10011	FEMRRI00WS	six-channel load cell

Table 23: Femoral load cell beams

The results of the load cells can be extracted as described in the following Table. The exact location of the load cells is shown in the figure below:





Figure 12: Upper and lower femur load cells

2.3.7 Knee load cells

The knee load cells can be used to determine the contact times. The load cells in the hardware are only one channel load cells.

Item	Beam-ID	Label	Channels in physical dummy
outboard knee load cell left	10012	KNEELEOUWS	one-channel load cell
outboard knee load cell right	10013	KNEERIOUWS	one-channel load cell
inboard knee load cell left	10014	KNEELEINWS	one-channel load cell
inboard knee load cell right	10015	KNEERIINWS	one-channel load cell

Table 24: Knee load cell beams



2.3.8 Tibia load cells

The tibias are also equipped with four load cells. Each tibia consists of two load cells, in the upper and the lower tibia. They are listed in the Table 25. The location of the load cells is depicted in the figure below:

Item	Beam- ID	Label	Channels in physical dummy
Upper tibia load cell left	10016	TIBILEUPWS	six-channel load cell
Upper tibia load cell right	10017	TIBIRIUPWS	six-channel load cell
Lower tibia load cell left	10018	TIBILELOWS	six-channel load cell
Lower tibia load cell right	10019	TIBIRILOWS	six-channel load cell

Table 25: Tibia load cell beams, left and right hand side





Figure 14: Tibia load cell beams

2.3.9 Spherical joint hip global force

The global force of the spherical joint hip left and right are new force and moment signals since WorldSID v5.0 in global coordinate system by beam 10255 and 10256.



Figure 15: Spherical joint hip global force beams

Item	Beam-ID	Label	Available components
Spherical joint hip left	10255	HIPJLE00WS	global force and moment
Spherical joint hip right	10256	HIPJRI00WS	global force and moment

Table 26: Spherical joint hip global force beams, left and right hand side



2.4 Deflections and rotations

In the WorldSID model, it is possible to measure deflections and also rotations of some parts. Therefore discrete elements, which have no stiffness, are used. The elements are only used for the purpose of measurement and do not influence the results of the model. The output of these elements is included in the DEFORC file. From the hardware SBL E1 the WorldSID is equipped with the 2D IR-TRACCs, i.e. the deflection and the rotation of the rib is measured. From LS-DYNA WorldSID v5.0 model offers the 2D IR-TRACCs measurement devices. From LS-DYNA WorldSID v7.0 model 1D IR-TRACCs are available again. LHD and RHD have different discrete elements which are used to measure the deflection and rotation of the Ribs.

2.4.1 Rib deflections 1D (up to hardware SBL E)



Figure 16: Cut through upper torso and location of rib deflection measurement springs

Item	Discrete	Label	Available components
	beam-ID		
shoulder rib LHD	10030	SH1DLE00WSDS0	change in length 1D
1. thorax rib LHD	10031	TR1DLE01WSDS0	change in length 1D
2. thorax rib LHD	10032	TR1DLE02WSDS0	change in length 1D
3. thorax rib LHD	10033	TR1DLE03WSDS0	change in length 1D
1. abdomen rib LHD	10034	AB1DLE01WSDS0	change in length 1D
2. abdomen rib LHD	10035	AB1DLE02WSDS0	change in length 1D
shoulder rib RHD	10300	SH1DRI00WSDS0	change in length 1D
1. thorax rib RHD	10301	TR1DRI01WSDS0	change in length 1D
2. thorax rib RHD	10302	TR1DRI02WSDS0	change in length 1D
3. thorax rib RHD	10303	TR1DRI03WSDS0	change in length 1D
1. abdomen rib RHD	10304	AB1DRI01WSDS0	change in length 1D
2. abdomen rib RHD	10305	AB1DRI02WSDS0	change in length 1D

Table 27: Rib deflection measurement using discrete elements (1D IR-TRACCs)



2.4.2 Rib deflections 2D (from hardware SBL E1)



Figure 17: Cut through upper torso and location of rib deflection measurement springs

Item	Discrete	Label	Available components
	beam-ID		
shoulder rib LHD	10060	SHRILE00WSDS0	change in length 2D
1. thorax rib LHD	10061	TRRILE01WSDS0	change in length 2D
2. thorax rib LHD	10062	TRRILE02WSDS0	change in length 2D
3. thorax rib LHD	10063	TRRILE03WSDS0	change in length 2D
1. abdomen rib LHD	10064	ABRILE01WSDS0	change in length 2D
2. abdomen rib LHD	10065	ABRILE02WSDS0	change in length 2D
shoulder rib RHD	10360	SHRIRI00WSDS0	change in length 2D
1. thorax rib RHD	10361	TRRIRI01WSDS0	change in length 2D
2. thorax rib RHD	10362	TRRIRI02WSDS0	change in length 2D
3. thorax rib RHD	10363	TRRIRI03WSDS0	change in length 2D
1. abdomen rib RHD	10364	ABRIRI01WSDS0	change in length 2D
2. abdomen rib RHD	10365	ABRIRI02WSDS0	change in length 2D

Table 28: Rib deflection measurement using discrete elements (2D IR-TRACCs)



Shoulder rib RHD discrete element for rotation 10320

First thorax rib RHD discrete element for rotation 10321

Second thorax rib RHD discrete element for _____ rotation 10322

Third thorax rib RHD discrete element for – rotation 10323

First abdomen rib RHD discrete element for rotation 10324

Second abdomen rib RHD discrete element for rotation 10325

Shoulder rib LHD discrete element for rotation 10050

First thorax rib LHD discrete element for rotation 10051

Second thorax rib LHD discrete element for rotation 10052

Third thorax rib LHD discrete element for rotation 10053

First abdomen rib LHD discrete element for rotation 10054 Second abdomen rib LHD discrete element for rotation 10055

Figure 18: Cut through upper torso and location of rib deflection measurement springs

Item	Discrete	Label	Available components
	Deam-ID		
shoulder rib LHD	10050	SHRILE00WSANZ	z-rotation
1. thorax rib LHD	10051	TRRILE01WSANZ	z-rotation
2. thorax rib LHD	10052	TRRILE02WSANZ	z-rotation
3. thorax rib LHD	10053	TRRILE03WSANZ	z-rotation
1. abdomen rib LHD	10054	ABRILE01WSANZ	z-rotation
2. abdomen rib LHD	10055	ABRILE02WSANZ	z-rotation
shoulder rib RHD	10320	SHRIRIOOWSANZ	z-rotation
1. thorax rib RHD	10321	TRRIRI01WSANZ	z-rotation
2. thorax rib RHD	10322	TRRIRI02WSANZ	z-rotation
3. thorax rib RHD	10323	TRRIRI03WSANZ	z-rotation
1. abdomen rib RHD	10324	ABRIRI01WSANZ	z-rotation
2. abdomen rib RHD	10325	ABRIRI02WSANZ	z-rotation





Since Version 6.0 there is additional rib x-rotation measurement in worldSID 50th model: Discrete elements are used to measure the X-Rotation of the Ribs.



Figure 19: upper torso and location of LHD rib x-rotation measurement springs

Item	Discrete	Label	Available components
	beam-ID		
shoulder rib LHD	10081	SHRILE00WSANX	x-rotation
1. thorax rib LHD	10082	TRRILE01WSANX	x-rotation
2. thorax rib LHD	10083	TRRILE02WSANX	x-rotation
3. thorax rib LHD	10084	TRRILE03WSANX	x-rotation
1. abdomen rib LHD	10085	ABRILE01WSANX	x-rotation
2. abdomen rib LHD	10086	ABRILE02WSANX	x-rotation

Table 30: LHD Rib X-rotation measurement using discrete elements (2D IR-TRACCs)





Figure 20: upper torso and location of RHD rib x-rotation measurement springs

Item	Discrete beam-ID	Label	Available components
shoulder rib RHD	10330	SHRIRI00WSANX	x-rotation
1. thorax rib RHD	10331	TRRIRI01WSANX	x-rotation
2. thorax rib RHD	10332	TRRIRI02WSANX	x-rotation
3. thorax rib RHD	10333	TRRIRI03WSANX	x-rotation
1. abdomen rib RHD	10334	ABRIRI01WSANX	x-rotation
2. abdomen rib RHD	10335	ABRIRI02WSANX	x-rotation

Table 31: RHD Rib X-rotation measurement using discrete elements (2D IR-TRACCs)

For EuroNCAP evaluation the local x- and y- deflections in respect to the spine box is calculated by an equation.

In simulation model we have added different nodes to evaluate the local x- and y- deflections directly form the nodout file for LHD and RHD. Nodes are defined:



Item	Node-ID	Label	Available components
shoulder rib	10751	shoulder rib deformation	x-, y-, z-displacement
	40750	Local X/Y/Z	
1. thorax rib	10752	1 thorax rib deformation	x-, y-, z-displacement
2 thorax rib	10753	2 thorax rib deformation	x- v- z-displacement
	10733	Local X/Y/Z	
3. thorax rib	10754	3 thorax rib deformation	x-, y-, z-displacement
		Local X/Y/Z	
1. abdomen rib	10755	1 abdomen rib	x-, y-, z-displacement
	10756	deformation Local X/Y/Z	
2. abdomen rib	10756	2 abdomen rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
shoulder rib	10781	shoulder right rib	x-, y-, z-displacement
RHD		deformation Local X/Y/Z	
1. thorax rib	10782	1 thorax right rib	x-, y-, z-displacement
RHD		deformation Local X/Y/Z	
2. thorax rib	10783	2 thorax right rib	x-, y-, z-displacement
RHD		deformation Local X/Y/Z	
thorax rib	10784	3 thorax right rib	x-, y-, z-displacement
RHD		deformation Local X/Y/Z	
1. abdomen rib	10785	1 abdomen right rib	x-, y-, z-displacement
RHD		deformation Local X/Y/Z	

Table 32: Rib local measurements in respect to Torso using nodout (2D IR-TRACCs)

The results of these nodes should give the same output than calculation the local deflections from resultant deflection and rotation of 2D IR-TRACCs.

2.4.3 Knee and ankle rotation

The WorldSID also offers the possibility to measure the relative rotations between the upper legs and the lower legs and also between the lower legs and the feet. Therefore discrete elements are additionally used to measure these rotations. The location of the elements in the model is depicted in the following figure.





Figure 21: Location of rotation measurement discrete beams in the WorldSID model

Item	Discrete beam-ID	Label	Available components
knee potentiometer y-	10040	KNEELE00WSANY	rotation
knee potentiometer y-	10041	KNEERI00WSANY	rotation
ankle potentiometer	10042	ANKLLE00WSANZ	rotation
ankle potentiometer	10043	ANKLRI00WSANZ	rotation
ankle potentiometer	10044	ANKLLE00WSANY	rotation
ankle potentiometer	10045	ANKLRI00WSANY	rotation
ankle potentiometer	10046	ANKLLE00WSANX	rotation
ankle potentiometer x-rotation right	10047	ANKLRI00WSANX	rotation

Table 33: Knee and ankle rotation measurement discrete beams



2.5 IR-TRACCs length and relative rotation

In the WorldSID model from version 5.0, it is possible to measure the length and relative rotation of IR-TRACCs.

These are measured by key word CONSTRAINED_JOINTSTIFFNESS_TRANSLATIONAL_TITLE and CONSTRAINED_JOINTSTIFFNESS_GENERALIZED_TITLE.

For evaluating signals of length use the output of the jntforc File. Then use type 0 and evaluate y- displacement.

For evaluating signals of relative rotation use the output of the jntforc File. Then use type 1 and evaluate z- displacement.

Some post processors show different component output name. In this case evaluate as follows:

For CONSTRAINED_JOINTSTIFFNESS_TRANSLATIONAL: theta_degree = y-displacement, length of 2D IR-TRACCs

For CONSTRAINED_JOINTSTIFFNESS_GENERALIZED: psi_degree = z-displacement, relative rotation degree of 2D IR-TRACCs

The CONSTRAINED_JOINT_STIFFNESS_TRANSLATIONAL cards IDs are shown as follows:

ID	Title	Local direction	component
1043	IR Tracc Shoulder rib length left	y-coordinate	theta_degree
1044	IR Tracc 1st Thorax rib length left	y-coordinate	theta_degree
1045	IR Tracc 2nd Thorax rib length left	y-coordinate	theta_degree
1046	IR Tracc 3rd Thorax rib length left	y-coordinate	theta_degree
1047	IR Tracc 1st Abdomen rib length left	y-coordinate	theta_degree
1048	IR Tracc 2nd Abdomen rib length left	y-coordinate	theta_degree
1057	IR Tracc Shoulder rib length right	y-coordinate	theta_degree
1058	IR Tracc 1st Thorax rib length right	y-coordinate	theta_degree
1059	IR Tracc 2nd Thorax rib length right	y-coordinate	theta_degree
1060	IR Tracc 3rd Thorax rib length right	y-coordinate	theta_degree
1061	IR Tracc 1st Abdomen rib length right	y-coordinate	theta_degree
1062	IR Tracc 2nd Abdomen rib length right	y-coordinate	theta_degree

Table 34: IR-TRACCs length evaluation

The CONSTRAINED_JOINT_STIFFNESS_GENERALIZED cards IDs are shown as follows:

ID	Title	Local rotation's direction	component
1051	IR Tracc Shoulder rib Rotation left	z-coordinate	psi_degree
1052	IR Tracc 1st Thorax rib Rotation left	z-coordinate	psi_degree
1053	IR Tracc 2nd Thorax rib Rotation left	z-coordinate	psi_degree
1054	IR Tracc 3rd Thorax rib Rotation left	z-coordinate	psi_degree
1055	IR Tracc 1st Abdomen rib Rotation left	z-coordinate	psi_degree



1056	IR Tracc 2nd Abdomen rib Rotation left	z-coordinate	psi_degree
1063	IR Tracc Shoulder rib Rotation right	z-coordinate	psi_degree
1064	IR Tracc 1st Thorax rib Rotation right	z-coordinate	psi_degree
1065	IR Tracc 2nd Thorax rib Rotation right	z-coordinate	psi_degree
1066	IR Tracc 3rd Thorax rib Rotation right	z-coordinate	psi_degree
1067	IR Tracc 1st Abdomen rib Rotation right	z-coordinate	psi_degree
1068	IR Tracc 2nd Abdomen rib Rotation right	z-coordinate	psi_degree

 Table 35:
 IR-TRACCs relative rotation evaluation



2.6 Pelvis Force

In the WorldSID model from version 7.0, it is possible to measure the bothe sides of pelvis force with more details. Pelvis bone is separated into small parts for evaluations over *CONTACT_FORCE_TRANSDUCER_PENALTY_ID. The small parts of left side and *C_FT_P_ID are shown in the following figure.



Figure 22: Pelvis left bone is separated into small parts for evaluations

Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1040	pelvis bone force left -	global contact force
		upper front	x-,y-,z-, resultant ;
Pelvis Force	1041	pelvis bone force left -	global contact force
		lower front	x-,y-,z-, resultant ;
Pelvis Force	1042	pelvis bone force left -	global contact force
		upper side forward	x-,y-,z-, resultant ;
Pelvis Force	1043	pelvis bone force left -	global contact force
		lower side forward	x-,y-,z-, resultant ;
Pelvis Force	1044	pelvis bone force left -	global contact force
		upper side middle	x-,y-,z-, resultant ;
Pelvis Force	1045	pelvis bone force left -	global contact force
		lower side middle	x-,y-,z-, resultant ;
Pelvis Force	1046	pelvis bone force left -	global contact force
		upper side rear	x-,y-,z-, resultant ;
Pelvis Force	1047	pelvis bone force left -	global contact force
		lower side rear	x-,y-,z-, resultant ;
Pelvis Force	1048	pelvis bone force left -	global contact force
		connection plate - upper	x-,y-,z-, resultant ;
Pelvis Force	1049	pelvis bone force left -	global contact force
		connection plate - lower	x-,y-,z-, resultant ;

Table 36: Pelvis force evaluations by *CONTACT_FORCE_TRANSDUCER_PENALTY_ID





The small parts of right side and *C_FT_P_ID are shown in the following figure.

Figure 23: Pelvis right bone is separated into small parts for evaluations

Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1060	pelvis bone force right -	global contact force
		upper front	x-,y-,z-, resultant ;
Pelvis Force	1061	pelvis bone force right -	global contact force
		lower front	x-,y-,z-, resultant ;
Pelvis Force	1062	pelvis bone force right -	global contact force
		upper side forward	x-,y-,z-, resultant ;
Pelvis Force	1063	pelvis bone force right -	global contact force
		lower side forward	x-,y-,z-, resultant ;
Pelvis Force	1064	pelvis bone force right -	global contact force
		upper side middle	x-,y-,z-, resultant ;
Pelvis Force	1065	pelvis bone force right -	global contact force
		lower side middle	x-,y-,z-, resultant ;
Pelvis Force	1066	pelvis bone force right -	global contact force
		upper side rear	x-,y-,z-, resultant ;
Pelvis Force	1067	pelvis bone force right -	global contact force
		lower side rear	x-,y-,z-, resultant ;
Pelvis Force	1068	pelvis bone force right -	global contact force
		connection plate - upper	x-,y-,z-, resultant ;
Pelvis Force	1069	pelvis bone force right -	global contact force
		connection plate - lower	x-,y-,z-, resultant ;

Table 37: Pelvis force evaluations by *CONTACT_FORCE_TRANSDUCER_PENALTY_ID



3. Incorporating the dummy into vehicle models

3.1 Positioning by preprocessor

The WorldSID model is delivered with a tree file for the Primer pre-processor (may also work for ALTAIR Hypermesh, BETA CAE-Systems ANSA and LS-PrePost, not verified by DYNAmore). This allows the user to position the dummy and adjust the parts according to their degrees of freedom. The Figure below shows the connections of movable parts via tree file. All revolute joints are visualized by beams.



Figure 24: Tree-file assemblies of the WorldSID model.

Two coordinate systems are modelled at the H-Point of the dummy model. These coordinate systems are connected to each other by a spherical joint. One coordinate system is constrained to global directions, which means only translations are possible, rotations are disabled. The other one is connected to the dummy, thus making it possible to measure the pelvis angle of the WorldSID during the positioning simulation quickly and easily. These coordinate systems are also used to determine the initial pelvis angle with Primer.

IV	viovable parts and revolute joints are:					
	assembly	stop angles				
	Foot, left and right about their ankle joints					
	local z-axis	stop angle: -29.0 and 29.0 degrees				
	Lower leg, left and right about their knee joints:					
	local y-axis	stop angle: -0.1 and 145.0 degrees				
	Upper leg bone, left and right about hip joint:					
	local x-axis	no stop angle				
	local y-axis	no stop angle				
	local z-axis	no stop angle				
	Torso	no stop angle				
	Head and neck	no stop angle				


Upper arm	no stop angle
Yoke	no stop angle

 Table 38: Movable parts of WorldSID by a pre-processor

The stop angles of the feet and the knees are adjusted to the physical range of motion of the individual components.

However it might be possible that some pre-processors do not support the stop function of this tree-file structure. In this case, initial penetrations can occur if the upper legs are rotated at the hip joints beyond the values given in Table 38. This reaction is based on the hardware. In the hardware, the geometry is deformed if the position of the upper leg is changed with respect to the pelvis.

The arms cannot be rotated in a pre-processor, because the jacket has to be deformed when the arms rotate. Here we recommend a pre-simulation to rotate the arm in the desired position.

The WorldSID V5.0 or high version model is also delivered with a MECHANISM in Primer for the position of 2D IR-TRACCs. This allows the user to position the 2D IR-TRACCs and adjust the parts according to their degrees and displacements freedom. This MECHANISM work for pre-processor (Primer, ALTAIR Hypermesh, BETA CAE-Systems ANSA...).

3.2 Positioning by pre-simulation

For the WorldSID v4.0 DYNAmore developed a new positioning pre-simulation procedure. The basic idea for this was to improve and simplify the usability of the dummy model. There are only a few steps necessary to achieve a correct positioned and ready-to-run WorldSID dummy model.

For the WorldSID v5.0 DYNAmore provide a new positioning pre-simulation procedure for 2D IR-TRACCs and optional thickness of damping material of thorax rib.

The procedure of positioning must be carried out strict as followed step:

<u>The first step</u> is to choice an optional thickness of damping material of thorax rib. This can be done by changing the parameter & trd_opt. Please see the detail in chapter 5.1 Release notes of WorldSID v5.0.

<u>The second step</u> is to adapt the posture of the dummy to your desired position besides the position of 2D IR-TRACCs in your car by using the preprocessor of your choice. You should not take care of penetrating parts and highly distorted elements. Save this dummy model to a separate file.





Figure 25: WorldSID origin position (left) and target position (right), besides 2D IR-TRACCs

<u>The third step</u> is to run the enclosed positioning script which is enclosed to the delivery package. The script needs the dummy model inputs of the origin and the target position. Run

psg_vX.X_... -d dummyinput_origin.key -t target_pos_dummy.key

The script generates a pre-simulation input for LS-DYNA. This one refers to the origin dummy model input (and also the license file) as a include file. The script is generating a BOUNDARY_PRESCRIBED_FINAL_GEOMETRY Card for the positions of Pelvis, Torso, Head/Neck and upper legs. For all other libs, there are generated spring and damper elements which pull the limbs in position.

<u>The fourth step</u> is to run the generated input in LS-DYNA and use the results for your actual car model or the position of 2D IR-TRACCs as the initial geometry when there isn't necessary to take care about the position of 2D IR-TRACCs.



Figure 26: WorldSID position after pre-simulation, besides 2D IR-TRACCs

The Results can be extracted by using any post processors. Only the new nodal coordinates are needed for the new position.



<u>The fifth step</u> is to adapt the posture of the dummy to your desired the position of 2D IR-TRACCs in your car by using the preprocessor of your choice. The same as the second step, you should not take care of penetrating parts and highly distorted elements. Save this dummy model also to a separate file.



Figure 27: WorldSID IR-TRACCs origin position (left) and target position (right)

<u>The sixth step</u> is the same the third step to run the enclosed positioning script which is enclosed to the delivery package. The script needs the dummy model inputs of the origin and the target position. Run

psg_vX.X_... -d dummyinput_origin.key -t target_pos_dummy.key

<u>The seventh step</u> is to run the generated input from the sixth step in LS-DYNA and use the results for your actual car model as the initial geometry.



Figure 28: WorldSID position after 2D IR-TRACCs pre-simulation

From Version 6.0, The thickness of thorax-rib's damping material can be also changed after the position of dummy.

A very helpful tool to replace the nodal coordinates in the original Input is plot2coor from the DYNAmore LS-DYNA Tools. This Tool can be requested on our Webpage here:



http://www.dynamore.de/en/products/tools

Pretentions are automatically applied by reference geometry so you do not have to take care about this.

3.3 Measurement of pelvis and torso angle

The pelvis, torso and head angles are measured in the physical WorldSID by three tilt sensors. These three sensors are also included in the model. They can be used to measure the pelvis and torso angle as shown in the following figure.





The initial position of the WorldSID model uses a pelvis angle of 14.5 degrees. For this position the H-Point tool, which is used to measure the pelvis angle without tilt sensor, has an angle of 45 degrees below the horizontal. For this pelvis angle, the torso (top of the lower neck bracket is horizontal) and head (upper neck load cell is horizontal) angle is zero degrees.

3.4 Numbering

- Nodes in the range of 10.000 to 11.000 are used for joints, accelerometers, ... definitions.
- Nodes with node IDs above 11.000 are used only in *NODE and *ELEMENT cards.
- Elements in the range of 10.000 to 11.000 are used for history, discrete elements, ... definitions.
- Elements with IDs above 11.000 are used only in *ELEMENT cards.

The numbering of the material tables and load curves is defined by parameters. The default range is given in Table 4: Model numbering scheme Table 4. If the model should be renumbered all tables and load curves must be renumbered by



using the parameter **wlcoff**. This parameter gives a numbering offset on all table IDs and load curve IDs.

3.5 Contact Definition

Please define a *CONTACT_AUTOMATIC_SURFACE_TO_SURFACE for the contact between dummy and seat (environment). We recommend the use of the SOFT 1 option of LS-DYNA, because this option shows a high robustness for contact between very stiff and very soft components. The WorldSID properties for this contact are defined in the part set 1500.

The second part set defined in the model (Part Set ID 1501) includes all parts of the model in it. This set can be used to exclude the model out of contacts, which are defined by the use of exclude part sets.

3.6 Additional Remarks

 The modification of the *CONTROL cards of the dummy file may have an influence on the performance and robustness of the model. Therefore the *CONTROL cards of the dummy models are proposed for integrated simulations as well.

Important flags on LS-DYNA control cards:

- CONTROL ACCURACY flag INN=2
- CONTROL BULK VISCOSITY flag TYPE=-1
- CONTROL SHELL flag ESORT=1
- CONTROL SOLID flag ESORT=1
- CONTROL_MPP_DECOMPOSITION_ARRANGE_PARTS
- If the CONTROL_MPP_DECOMPOSITION_ARRANGE_PARTS is erased from the model the simulation time in large models can be two or three times longer. It is strongly recommended to use this control card in MPP simulations.
- The model should be used with a time step size of 0.7 microseconds or less!
- If a model for right side impact is needed, please contact DYNAmore. RHD models in both systems of units are available.
- All nodes are connected to an element, except the third beam nodes of the beam elements.
- No mass less nodes are present in the input file of the dummy except the third beam nodes of the beam elements.
- The model is free of initial penetrations.
- The Version 4.0 and higher of the WorldSID provides parameters to scale the friction of the joint off all limbs. As default a 1 g adjustment of the



joints is included. The user is now able to increase or decrease the friction values of the joints. The scale factors are used for the left and right hand side assemblies. So it is not possible to scale left and right assembly different.

Parameter name	Joint
sfarmx	Scale factor arms local x-rotation
sfarmy	Scale factor arms local y-rotation
sffemr	Scale factor upper legs all directions
sfknee	Scale factor knees
sfankl	Scale factor ankle joins all directions

Table 39: Parameters to scale joint friction



4. License file and usage

The WorldSID is distributed with a license file which uses an expiry date. The license file is sent to the user with the whole dummy package. It is a PGP encrypted part of the dummy model input and includes all load curves referenced in the WorldSID model. For the WorldSID there is a general license file for any unit system provided.

There are parameters defined which can be used to offset the numbering of the load curves. The load curves can be scaled by using parameters provided in the main WorldSID input. The names of the parameters refer to the table or load curve ID of each material. So if the values of the table ID 1002 are to be scaled then the parameter ws1002 should be used.

The principle structure is as follows:

Input data in the WorldSID license file:

*PARAMETER
\$ Load Curve offset
I wloff 0
\$ Load Curve scale values

R wsXXXX1.0R wsxXXXX1.0

Input of the license file:

*PARAMETER_E I lcTABID R eTABID	XPRESSION TABID + &w] 1.0 * & ws}	loff XXXX		
*DEFINE_CURV	E			
&lcTABID <v< td=""><td>0 alues_x></td><td>1.0&eTABID <values_y></values_y></td><td>0.0</td><td>0.0</td></v<>	0 alues_x>	1.0&eTABID <values_y></values_y>	0.0	0.0
	•			

The license file must be included like a normal include file. But it is necessary that the license file is included **IN** the WorldSID model main file **AFTER** the *PARMETER block. If you get error messages like "missing parameter" you should check if the license file is included at the correct position in the file.

The expiry date and the owner of the license are printed out in the message file of LS-DYNA. The name of the license file also includes the company name and the expiry date of the dummy.



We recommend storing the license file of dummy models in a central place as read only. Furthermore the name of the license include should be simple like for instance

wsid50_v7.1_all_units_server.asc.

With a symbolic link from the current license to this name it is possible to keep older input decks running without updating the input data of them.

For the work in a pre-processor, an additional file is delivered:

wsid50_pdb_v7.1_all_units_load_curves_work.key

This work file includes the same input as the encrypted license file. The only difference is the scaling of the load curves in the work file. The load curves are scaled randomly in a wrong range and they are much too soft to be used for a LS_DYNA simulation. But the file can be used to observe the quality and course of the material curves.

A LS-DYNA simulation in use of the work file will give wrong results and is very unstable. So if you observe dummy model crashes without appreciable load you should check if you included the load-curves-work file instead of the license file.



5. Release Notes

5.1 Release notes of WorldSID v7.0 and v7.1

- Update version 7.1
 - Different Material curve optimization.
 - Pelvis Contact und Material fixed.
 - Friction parameters of right side thorax are adjusted.
 - The update's purpose is to improve the stable of the model, there don't have influences on the simulation curve of the model.
- Geometric modifications



• Finer neck, from 3mm~9mm to 2.5mm



 \circ Finer thorax





 $\circ~$ Finer thorax-Pad, from 8mm to 4mm, in order to compare to finer thorax rib and jacket



WSID v7 .0

WSID v6.0





 Solid rib couple: Rib couple is modified from shell elements to two layers solid elements with MAT 181 simplified rubber





 \circ Finer pelvis and iliac wing



WSID50th V6.0 has just one side for iliac wing force evaluation.

WSID50th V7.0 has both sides.

Constrained_method for optional thorax_rib_damping_mat_nodes:

The optional nodes are constrained by: *CONSTRAINED_NODAL_RIGID_BODY

This feature is available for both side of thorax-rib's damping material from version 7.0.



The control-parameter of thickness of thorax-rib's damping material is still the &trd_opt and located at the first place of block *PARAMETER.



 LHD, RHD in one master Input from v7.0. IR_TRACCs, Ballast for 2D IR_TRACCs, RibEye System are separated as include files for LHD and RHD.

Delivery package v6.0 include 4 models: S3, S3_RHD, S2, S2_RHD. Delivery package v7.0 include just 2 models: S3 and S2.

Include files for v6.0 in each model	Include files for v7.0 in each model
License(asc file) / Load curves file	License(asc file) / Load curves file
Arm sleeve	Arm sleeve
H-point tool	H-point tool
RibEye / RibEye_RHD	RibEye_LHD / RibEye_RHD
	IR_TRACCs_LHD / IR_TRACCs_RHD
	Ballast_LHD / Ballast_RHD

IR_TRACCs, Ballast, RibEye System includes for WSID50th V7.0 and subsequent version:

a. worldSID50_pdb_vx.x.x_mm_ms_kg_IR-TRACC_left_vx.x.key / worldSID50_pdb_vx.x.x_mm_s_ton_IR-TRACC_left_vx.x.key

- b. worldSID50_pdb_vx.x.x_mm_ms_kg_IR-TRACC_right_vx.x.key
- / worldSID50_pdb_vx.x.x_mm_s_ton_IR-TRACC_right_vx.x.key
- c. worldSID50_pdb_vx.x.x_Ballast_left_vx.x.key
- d. worldSID50_pdb_vx.x.x_Ballast_right_vx.x.key
- e. worldSID50_pdb_vx.x.x_mm_ms_kg_RibEye_left_vx.x.key / worldSID50_pdb_vx.x.x_mm_s_ton_RibEye_left_vx.x.key
- f. worldSID50_pdb_vx.x.x_mm_ms_kg_RibEye_right_vx.x.key / worldSID50_pdb_vx.x.x_mm_s_ton_RibEye_right_vx.x.key

For LHD model we just need includes **a**, **d** and **e**. For RHD model we just need includes **b**, **c** and **f**.



• 1D IR_TRACCs are available again from WSID50th V7.0. LHD and RHD have different discrete elements which are used to measure the deflection and rotation of the Ribs

Item	Discrete beam-ID	Label	Available components
shoulder rib LHD	10030	SH1DLE00WSDS0	change in length 1D
1. thorax rib LHD	10031	TR1DLE01WSDS0	change in length 1D
2. thorax rib LHD	10032	TR1DLE02WSDS0	change in length 1D
3. thorax rib LHD	10033	TR1DLE03WSDS0	change in length 1D
1. abdomen rib LHD	10034	AB1DLE01WSDS0	change in length 1D
2. abdomen rib LHD	10035	AB1DLE02WSDS0	change in length 1D
shoulder rib LHD	10050	SHRILE00WSANZ	z-rotation
1. thorax rib LHD	10051	TRRILE01WSANZ	z-rotation
2. thorax rib LHD	10052	TRRILE02WSANZ	z-rotation
3. thorax rib LHD	10053	TRRILE03WSANZ	z-rotation
1. abdomen rib LHD	10054	ABRILE01WSANZ	z-rotation
2. abdomen rib LHD	10055	ABRILE02WSANZ	z-rotation
shoulder rib LHD	10060	SHRILE00WSDS0	change in length 2D
1. thorax rib LHD	10061	TRRILE01WSDS0	change in length 2D
2. thorax rib LHD	10062	TRRILE02WSDS0	change in length 2D
3. thorax rib LHD	10063	TRRILE03WSDS0	change in length 2D
1. abdomen rib LHD	10064	ABRILE01WSDS0	change in length 2D
2. abdomen rib LHD	10065	ABRILE02WSDS0	change in length 2D
shoulder rib LHD	10081	SHRILE00WSANX	x-rotation
1. thorax rib LHD	10082	TRRILE01WSANX	x-rotation
2. thorax rib LHD	10083	TRRILE02WSANX	x-rotation
3. thorax rib LHD	10084	TRRILE03WSANX	x-rotation
1. abdomen rib LHD	10085	ABRILE01WSANX	x-rotation
2. abdomen rib LHD	10086	ABRILE02WSANX	x-rotation
shoulder rib RHD	10300	SH1DRI00WSDS0	change in length 1D
1. thorax rib RHD	10301	TR1DRI01WSDS0	change in length 1D
2. thorax rib RHD	10302	TR1DRI02WSDS0	change in length 1D
3. thorax rib RHD	10303	TR1DRI03WSDS0	change in length 1D
1. abdomen rib RHD	10304	AB1DRI01WSDS0	change in length 1D
2. abdomen rib RHD	10305	AB1DRI02WSDS0	change in length 1D
shoulder rib RHD	10320	SHRIRIOOWSANZ	z-rotation
1. thorax rib RHD	10321	TRRIRI01WSANZ	z-rotation
2. thorax rib RHD	10322	TRRIRI02WSANZ	z-rotation
3. thorax rib RHD	10323	TRRIRI03WSANZ	z-rotation
1. abdomen rib RHD	10324	ABRIRI01WSANZ	z-rotation
2. abdomen rib RHD	10325	ABRIRI02WSANZ	z-rotation
shoulder rib RHD	10330	SHRIRIOOWSANX	x-rotation
1. thorax rib RHD	10331	TRRIRI01WSANX	x-rotation
2. thorax rib RHD	10332	TRRIRI02WSANX	x-rotation
3. thorax rib RHD	10333	TRRIRI03WSANX	x-rotation
1. abdomen rib RHD	10334	ABRIRI01WSANX	x-rotation
2. abdomen rib RHD	10335	ABRIRI02WSANX	x-rotation
shoulder rib RHD	10360	SHRIRI00WSDS0	change in length 2D
1. thorax rib RHD	10361	TRRIRI01WSDS0	change in length 2D
2. thorax rib RHD	10362	TRRIRI02WSDS0	change in length 2D
3. thorax rib RHD	10363	TRRIRI03WSDS0	change in length 2D
1. abdomen rib RHD	10364	ABRIRI01WSDS0	change in length 2D
2. abdomen rib RHD	10365	ABRIRI02WSDS0	change in length 2D



For EuroNCAP evaluation the local x- and y- deflections in respect to the spine box is calculated by an equation.

In simulation model we have added different nodes to evaluate the local x- and y- deflections directly form the nodout file for LHD and RHD. Nodes are defined:

Item	Node-ID	Label	Available components
shoulder rib LHD	10751	shoulder left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
1. thorax rib LHD	10752	1 thorax left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
2. thorax rib LHD	10753	2 thorax left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
3. thorax rib LHD	10754	3 thorax left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
1. abdomen rib LHD	10755	1 abdomen left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
2. abdomen rib LHD	10756	2 abdomen left rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
shoulder rib RHD	10781	shoulder right rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
1. thorax rib RHD	10782	1 thorax right rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
2. thorax rib RHD	10783	2 thorax right rib	x-, y-, z-displacement
		deformation Local X/Y/Z	
3. thorax rib RHD	10784	3 thorax right rib	x-, y-, z-displacement
	40705	deformation Local X/Y/Z	
1. abdomen rib RHD	10785	1 abdomen right rib	x-, y-, z-displacement
	10706	deformation Local X/Y/Z	
2. abdomen rib RHD	10/86	2 abdomen right rib	x-, y-, z-displacement
		deformation Local X/Y/Z	

In the WorldSID model from version 7.0, the measurement of the length and relative rotation of IR-TRACCs are available for both side (LHD and RHD).

These are measured by key word

CONSTRAINED_JOINTSTIFFNESS_TRANSLATIONAL_TITLE and CONSTRAINED_JOINTSTIFFNESS_GENERALIZED_TITLE.

The CONSTRAINED_JOINT_STIFFNESS_TRANSLATIONAL cards IDs are shown as follows:

ID	Title	Local direction	component
1043	IR Tracc Shoulder rib length left	y-coordinate	theta_degree
1044	IR Tracc 1st Thorax rib length left	y-coordinate	theta_degree
1045	IR Tracc 2nd Thorax rib length left	y-coordinate	theta_degree
1046	IR Tracc 3rd Thorax rib length left	y-coordinate	theta_degree
1047	IR Tracc 1st Abdomen rib length left	y-coordinate	theta_degree
1048	IR Tracc 2nd Abdomen rib length left	y-coordinate	theta_degree
1057	IR Tracc Shoulder rib length right	y-coordinate	theta_degree
1058	IR Tracc 1st Thorax rib length right	y-coordinate	theta_degree
1059	IR Tracc 2nd Thorax rib length right	y-coordinate	theta_degree
1060	IR Tracc 3rd Thorax rib length right	y-coordinate	theta_degree
1061	IR Tracc 1st Abdomen rib length right	y-coordinate	theta_degree
1062	IR Tracc 2nd Abdomen rib length right	y-coordinate	theta_degree



The CONSTRAINED_JOINT_STIFFNESS_GENERALIZED cards IDs are shown as follows:

ID	Title	Local rotation's direction	component
1051	IR Tracc Shoulder rib Rotation left	z-coordinate	psi_degree
1052	IR Tracc 1st Thorax rib Rotation left	z-coordinate	psi_degree
1053	IR Tracc 2nd Thorax rib Rotation left	z-coordinate	psi_degree
1054	IR Tracc 3rd Thorax rib Rotation left	z-coordinate	psi_degree
1055	IR Tracc 1st Abdomen rib Rotation left	z-coordinate	psi_degree
1056	IR Tracc 2nd Abdomen rib Rotation left	z-coordinate	psi_degree
1063	IR Tracc Shoulder rib Rotation right	z-coordinate	psi_degree
1064	IR Tracc 1st Thorax rib Rotation right	z-coordinate	psi_degree
1065	IR Tracc 2nd Thorax rib Rotation right	z-coordinate	psi_degree
1066	IR Tracc 3rd Thorax rib Rotation right	z-coordinate	psi_degree
1067	IR Tracc 1st Abdomen rib Rotation right	z-coordinate	psi_degree
1068	IR Tracc 2nd Abdomen rib Rotation right	z-coordinate	psi_degree

 In the WorldSID model from version 7.0, the measurement of the pelvis force are available for both sides (LHD and RHD). Pelvis bone is separated into small parts for evaluations through *CONTACT_FORCE_TRANSDUCER_PENALTY_ID.

The small parts of left side and *C_FT_P_ID are shown in the following:





Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1040	pelvis bone force left -	global contact force
		upper front	x-,y-,z-, resultant ;
Pelvis Force	1041	pelvis bone force left -	global contact force
		lower front	x-,y-,z-, resultant ;
Pelvis Force	1042	pelvis bone force left -	global contact force
		upper side forward	x-,y-,z-, resultant ;
Pelvis Force	1043	pelvis bone force left -	global contact force
		lower side forward	x-,y-,z-, resultant ;
Pelvis Force	1044	pelvis bone force left -	global contact force
		upper side middle	x-,y-,z-, resultant ;
Pelvis Force	1045	pelvis bone force left -	global contact force
		lower side middle	x-,y-,z-, resultant ;
Pelvis Force	1046	pelvis bone force left -	global contact force
		upper side rear	x-,y-,z-, resultant ;
Pelvis Force	1047	pelvis bone force left -	global contact force
		lower side rear	x-,y-,z-, resultant ;
Pelvis Force	1048	pelvis bone force left -	global contact force
		connection plate - upper	x-,y-,z-, resultant ;
Pelvis Force	1049	pelvis bone force left -	global contact force
		connection plate - lower	x-,y-,z-, resultant ;

The small parts of right side and $*C_FT_P_ID$ are shown in the following:





Item	CETPID	Lahel	Available components
Pelvis Force	1060	pelvis bone force right -	global contact force
I EIVIS I UICE	1000	upper front	
Dolvis Forco	1061	polyic bono forco right	alobal contact force
FEIVIS I UICE	1001	lower front	
Dali da Fanas	1000		x-,y-,2-, resultant,
Peivis Force	1062	peivis bone force right -	global contact force
	1000	upper side forward	x-,y-,z-, resultant ;
Pelvis Force	1063	pelvis bone force right -	global contact force
		lower side forward	x-,y-,z-, resultant ;
Pelvis Force	1064	pelvis bone force right -	global contact force
		upper side middle	x-,y-,z-, resultant ;
Pelvis Force	1065	pelvis bone force right -	global contact force
		lower side middle	x-,y-,z-, resultant ;
Pelvis Force	1066	pelvis bone force right -	global contact force
		upper side rear	x-,y-,z-, resultant ;
Pelvis Force	1067	pelvis bone force right -	global contact force
		lower side rear	x-,y-,z-, resultant ;
Pelvis Force	1068	pelvis bone force right -	global contact force
		connection plate - upper	x-,y-,z-, resultant ;
Pelvis Force	1069	pelvis bone force right -	global contact force
		connection plate - lower	x-,y-,z-, resultant ;

- Soft 2 for dummy self contact.
- Jacket is adapted to new mesh and contact definition.
- Arm model optimization.
- Lumbar model optimization.
- Material model optimization for different parts
- Time step is changed to 7E-4ms



5.2 Release notes of WorldSID v6.0

- Update v6.0.2: Lumped mass is assigned to nodes of optional thickness of thorax rib damping material with Keyword *ELEMENT_MASS_NODE_SET in order to avoid massless nodes.
- Update v6.0.2: Model clean up, Empty data are removed (include *PART, *SECTION, *DEFINE_COORDINATE_NODES, *BEAM with free node).
- Dummy mechanism update: Hardware status for location of Pelvis Zero is: H-point tool oriented at 45 degree in Y direction and now the output of pelvis' tilt sensor is 0 degree. H-point tool position from delivery package of WSID50th model is always located at 45 degree in Y direction, and model position of delivery package is also located at Pelvis Zero.

The output of the delivery position of pelvis angle was changed from 15 degree to 0 degree. The dummy position was not changed, just the output of this position, the output of old pelvis' tilt sensor is 15 degree.



WorldSID50th deliver position: H-Point tool, Pelvis Zero

Mechanism update show in primer:

WSID50th V6.0

WSID50th V6.0.1

1: Global Coordinate Sys	0.0	0.0	0.0	1: Global Coordinate Sys	0.0	0.0	0.0
2: Pelvis	0.0	15.0	0.0	2: Pelvis	0.0	0.0	0.0
3: Torso	0.0	-0.0	0.0	3: Torso	0.0	-0.0	0.0
4: Head and Neck	0.0	0.0	0.0	4: Head and Neck	0.0	0.0	0.0
9: Femur left	-0.0	0.0	-0.0	9: Femur left	-0.0	0.0	-0.0
10: Femur right	0.0	0.0	0.0	10: Femur right	0.0	0.0	0.0



• The Right_Hand_Dummy model has the same coordinate system as the Left_Hand_Dummy model for output. Both base on SAE J211.





- Geometric modifications
 - \circ $\;$ Half arm is with new mesh and some material are updated.



• Shoulder PAD geometric update





• New half arm has better deformation behavior in shoulder area. In the following a sled test is shown for both versions of WorldSID: Focus on the arm_joint hole





• Jacket is weared tight with initial stress.



Jacket Performance in sled test: Flat barrier and arm second notch WSID v5.0 v6.0







• Rib x-rotation measurement: Discrete elements are used to measure the X-Rotation of the Ribs





Item	Discrete beam- ID	Label	Available components
shoulder rib	10081	SHRILE00WSANX	x-rotation
1. thorax rib	10082	TRRILE01WSANX	x-rotation
2. thorax rib	10083	TRRILE02WSANX	x-rotation
3. thorax rib	10084	TRRILE03WSANX	x-rotation
1. abdomen rib	10085	ABRILE01WSANX	x-rotation
2. abdomen rib	10086	ABRILE02WSANX	x-rotation

 Constrained_method for optional thorax_rib_damping_mat_nodes: (Since version 5.0 thickness of thorax-rib's damping material is variable by parameter trd_opt.)

Version 5.0: The optional nodes are constrained by:

*CONSTRAINED_EXTRA_NODES_SET

Version 6.0: The optional nodes are constrained by:

*CONSTRAINED_NODAL_RIGID_BODY

The thickness of thorax-rib's damping material can be changed after the position of dummy in version 6.0.

Update since version 6.0.1:

SET_NODE (trd_opt_nodes) was defined for extra nodes of optional thickness of thorax rib damping material, in order to hold these extra nodes together with dummy when there is an initial moving for dummy position in preprocessor. This is an update for Dummy mechanism.

WSID v5.0

v6.0





5.3 Release notes of WorldSID v5.0

- 1D IR-TRACCs are deleted from WorldSID v5.0. 1D IR-TRACC is the old standard hardware. Rib deflection is measured by 2D IR-TRACCs right now for WorldSID 50th, both of hardware and software.
- *CONSTRAINED_JOINT_STIFFNESS... of 2D IR-TRACCs are modified to deal with the blocked and NAN problem in IR-TRACCs.
- MECHANISM for IR-TRACCs are created. This is for IR-TRACCs initial position and work for pre-processor (Primer, ALTAIR Hypermesh, BETA CAE-Systems ANSA...).
- Thickness of thorax-rib's damping material is variable by parameter.

The control-parameter is &trd_opt and located at the first place of block *PARAMETER. There are 4 difference optional thickness for thorax-rib which can be chosen by changing the parameter &trd_opt.

&trd_opt == 1: The thickness of thorax rib (Damp-MAT) is 3.00mm. &trd_opt == 2: The thickness of thorax rib (Damp-MAT) is 3.45mm. &trd_opt == 3: The thickness of thorax rib (Damp-MAT) is 3.90mm. &trd_opt == 4: The thickness of thorax rib (Damp-MAT) is 4.35mm.

Original thickness of thorax-rib's damping material is 3.00mm after calibration.

Very important comment: !!!!!

- WorldSID v5.0 is defined with control parameter of thickness of thorax-rib's damping material. The nodes ID and elements ID in WorldSID v5.0 can't be renumbered. For number crash problem and number range distribution: WorldSID v5.0 must be included by keyword *INCLUDE_TRANSFORM.
- WorldSID v5.0 provide the function of pre-position for 2D IR-TRACCs (rib pre-position). Before the simulation of rib pre-position, the thickness of thorax-rib's damping material must be chosen. After the simulation of rib pre-position, the control-parameter &trd_opt can't be changed anymore, one simulation of rib pre-position according to just only one thickness of thorax-rib's damping material.
- Geometric modifications
 - Symmetry jacket, This finer jacket is optimal for EuroNCAP Far-Side simulation.





• Thorax rib coupler geometric update



• Arm-sleeve is a include key-file in WorldSID v5.0. This can be switched very easy in dummy-key-file. Without arm-sleeve model is stander model for EuroNCAP Far-side test.

This include file is: worldSID50_pdb_vx.x_arm_sleeve_vx.x.key





With arm-sleeve

Without arm-sleeve

• Arm validation is improved. WSID v4.0 still has a relative soft half arm. The bending behavior of arm is improved in WSID v5.0. In the following a half-arm component test is shown for both versions of WorldSID:







v5.0





- ISO-CODE-Label are created for evaluation to instead of the old evaluation's label.
 - *DATABSE_HISTORY_NODE_ID, evaluation for acceleration or angel.



Item	Node-ID	Old Label	ISO-CODE
Head	10001	accelerometer head	HEAD0000WSAC
T1	10002	accelerometer T1	THSP0100WSAC
T4	10003	accelerometer T4	THSP0400WSAC
T12	10004	accelerometer T12	THSP1200WSAC
Pelvis	10005	accelerometer pelvis	PELV0000WSAC
Head	10006	rotational accelerometer Head	HEAD0000WSAA
Thorax	10007	rotational accelerometer Thorax	THSP0000WSAA
Pelvis	10008	rotational accelerometer Pelvis	PELV0000WSAA
shoulder rib	10010	accelerometer shoulder rib left	SHRILE00WSAC
1. thorax rib	10011	accelerometer upper thorax rib left	TRRILE01WSAC
2. thorax rib	10012	accelerometer middle thorax rib left	TRRILE02WSAC
3. thorax rib	10013	accelerometer lower thorax rib left	TRRILE03WSAC
1. abdomen rib	10014	accelerometer upper abdomen rib left	ABRILE01WSAC
2. abdomen rib	10015	accelerometer lower abdomen rib left	ABRILE02WSAC
shoulder rib	10020	accelerometer shoulder rib right	SHRIRI00WSAC
1. thorax rib	10021	accelerometer upper thorax rib	THRIRI01WSAC
2. thorax rib	10022	accelerometer middle thorax rib	THRIRI02WSAC
3. thorax rib	10023	accelerometer lower thorax rib	THRIRI03WSAC
1. abdomen	10024	accelerometer upper abdomen	ABRIRI01WSAC
rib		rib right	
2. abdomen	10025	accelerometer lower abdomen	ABRIRI02WSAC
rib		rib right	
Tibia	10101	accelerometer tibia left	TIBILE00WSAC
Tibia	10102	accelerometer tibia right	TIBIRIOOWSAC

• *DATABSE_HISTORY_BEAM_ID, evaluation for force and moment.

Item	Beam-ID	Old Label	ISO-CODE
Upper neck load cell	10000	upper neck load cell	NECKUP00WS
Lower neck load cell	10001	lower neck load cell	NECKLO00WS
Left shoulder load	10002	shoulder load cell left	SHLDLE00WS
Right shoulder load cell	10003	shoulder load cell right	SHLDRI00WS
Lumbar load cell	10004	lumbar load cell	LUSP0000WS
Sacro-iliac load cell left hand side	10005	sacro-iliac load cell left	SACRLE00WS
Sacro-iliac load cell right hand side	10006	sacro-iliac load cell right	SACRRI00WS
Pubic symphysis load cell	10007	pubic load cell	PUBC0000WS



Femoral neck load	10008	femoral neck load cell	FEACLE00WS
Femoral neck load	10009	femoral neck load cell	FEACRI00WS
cell right hand side		right	
Femur load cell left	10010	femur load cell left	FEMRLE00WS
hand side			
Femur load cell right	10011	femur load cell right	FEMRRI00WS
hand side			
outboard knee load	10012	outer knee contact load	KNEELEOUWS
cell left		cell left	
outboard knee load	10013	outer knee contact load	KNEERIOUWS
cell right		cell right	
inboard knee load	10014	inner knee contact load	KNEELEINWS
cell left		cell left	
inboard knee load	10015	inner knee contact load	KNEERIINWS
cell right		cell right	
Upper tibia load cell	10016	upper tibia load cell left	TIBILEUPWS
left			
Upper tibia load cell	10017	upper tibia load cell right	TIBIRIUPWS
right			
Lower tibia load cell	10018	lower tibia load cell left	TIBILELOWS
left			
Lower tibia load cell	10019	lower tibia load cell right	TIBIRILOWS
right			

*DATABASE_HISTORY_DISCRETE_ID instead of
 *DATABASE_HISTORY_DISCRETE, evaluation for deflection

Item	Discrete beam-ID	Old Label	ISO-CODE
shoulder rib deformation	10060	no label	SHRILE00WSDS0
1. thorax rib deformation	10061	no label	TRRILE01WSDS0
2. thorax rib deformation	10062	no label	TRRILE02WSDS0
3. thorax rib deformation	10063	no label	TRRILE03WSDS0
1. abdomen rib	10064	no label	ABRILE01WSDS0
deformation			
2. abdomen rib	10065	no label	ABRILE02WSDS0
deformation			
shoulder rib rotation Z	10050	no label	SHRILE00WSANZ
1. thorax rib rotation Z	10051	no label	TRRILE01WSANZ
2. thorax rib rotation Z	10052	no label	TRRILE02WSANZ
3. thorax rib rotation Z	10053	no label	TRRILE03WSANZ
1. abdomen rib rotation Z	10054	no label	ABRILE01WSANZ
2. abdomen rib rotation Z	10055	no label	ABRILE02WSANZ
knee potentiometer y-	10040	no label	KNEELE00WSANY
rotation left			
knee potentiometer y-	10041	no label	KNEERI00WSANY
rotation right			
ankle potentiometer z-	10042	no label	ANKLLE00WSANZ
rotation left			
ankle potentiometer z-	10043	no label	ANKLRI00WSANZ
rotation right			

Release Notes



ankle potentiometer y- rotation left	10044	no label	ANKLLE00WSANY
ankle potentiometer y-	10045	no label	ANKLRI00WSANY
ankle potentiometer x-	10046	no label	ANKLLE00WSANX
ankle potentiometer x- rotation right	10047	no label	ANKLRIOOWSANX

• WorldSID v5.0 provide the global node data of the middle point of marker in output data NODOUT.

Head right node ID 10051	
	Head left node ID 10050
Shoulder right node ID 1005	3
53	Shoulder left node ID 10052
Arm-sleeve right node ID 10049	E E PA
Arm end right node ID 10055	Arm-sleeve left node ID 10048
H-point right node ID 10057	Arm end left node ID 10054
Outer knee right node ID 10059	H-point left node ID 10056
Inner knee right	2 - 2
	Outer knee left node ID 10058
Outer ankle right node ID 10063	Inner knee left node ID 10060
	- Inner ankle left node ID 10064
Inner ankle right node ID 10065	Outer ankle left node ID 10062



Item	Node-ID	Label	Available components
marker sleeve-shoulder	10048	SLEELEMAWSAC	global node output
left			
marker sleeve-shoulder	10049	SLEERIMAWSAC	global node output
right			
marker head left	10050	HEADLEMAWSAC	global node output
marker head right	10051	HEADRIMAWSAC	global node output
marker arm-shoulder	10052	SHLDLEMAWSAC	global node output
marker arm-shoulder	10053	SHI DRIMAWSAC	alobal node output
right	10055		
marker arm end left	10054	ARMOLEMAWSAC	alobal node output
marker arm end right	10055	ARMORIMAWSAC	global node output
marker H-point left	10056	PELVLEMAWSAC	global node output
marker H-point right	10057	PELVRIMAWSAC	global node output
marker outer knee left	10058	KNEELEMOWSAC	global node output
marker outer knee	10059	KNEERIMOWSAC	global node output
right			
marker inner knee left	10060	KNEELEMIWSAC	global node output
marker inner knee	10061	KNEERIMIWSAC	global node output
right			
marker outer ankle left	10062	ANKLLEMOWSAC	global node output
marker outer ankle	10063	ANKLRIMOWSAC	global node output
right			
marker inner ankle left	10064	ANKLLEMIWSAC	global node output
marker inner ankle	10065	ANKLRIMIWSAC	global node output
right			

• The global force of the spherical joint hip left and right are new force and moment signals for WorldSID v5.0 in global coordinate system by beam 10255 and 10256.



Spherical joint hip left beam 10255

The Beam are:

Item	Beam-ID	Label	Available components
Spherical joint hip left	10255	HIPJLE00WS	global force and moment
Spherical joint hip right	10256	HIPJRI00WS	global force and moment



• Second nodes of accelerometer for Head, T1, T4, T12 and Pelvis in global output.



The nodes are:

Item	Node-ID	Label	Available components
Head global	10123	HEAD00GBWSAC	global x-,y-,z- acceleration
T1 global	10139	THSP01GBWSAC	global x-,y-,z- acceleration
T4 global	10140	THSP04GBWSAC	global x-,y-,z- acceleration
T12 global	10141	THSP12GBWSAC	global x-,y-,z- acceleration
Pelvis global	10142	PELV00GBWSAC	global x-,y-,z- acceleration



• Length and relative rotation of IR-TRACCs

There is evaluation method for the length and relative rotation of 2D IR-TRACCs from WorldSID 50th v5.0 which are measured by key word CONSTRAINED_JOINTSTIFFNESS_TRANSLATIONAL_TITLE and CONSTRAINED_JOINTSTIFFNESS_GENERALIZED_TITLE.

For evaluating signals of length use the output of the jntforc File. Then use type 0 and evaluate y- displacement.

For evaluating signals of relative rotation use the output of the jntforc File. Then use type 1 and evaluate z- displacement.

Some post processors show different component output name. In this case evaluate as follows:

For CONSTRAINED_JOINTSTIFFNESS_TRANSLATIONAL: theta_degree = y-displacement, length of 2D IR-TRACCs

For CONSTRAINED_JOINTSTIFFNESS_GENERALIZED: psi_degree = z-displacement, relative rotation degree of 2D IR-TRACCs

The CONSTRAINED_JOINT_STIFFNESS_TRANSLATIONAL cards IDs are as follows:

ID	Title	Local direction	component
1043	IR Tracc Shoulder rib length	y-coordinate	theta_degree
1044	IR Tracc 1st Thorax rib length	y-coordinate	theta_degree
1045	IR Tracc 2nd Thorax rib length	y-coordinate	theta_degree
1046	IR Tracc 3rd Thorax rib length	y-coordinate	theta_degree
1047	IR Tracc 1st Abdomen rib length	y-coordinate	theta_degree
1048	IR Tracc 2nd Abdomen rib length	y-coordinate	theta_degree

The CONSTRAINED_JOINT_STIFFNESS_GENERALIZED cards IDs are as follows:

ID	Title	Local rotation's direction	component
1051	IR Tracc Shoulder rib Rotation	z-coordinate	psi_degree
1052	IR Tracc 1st Thorax rib Rotation	z-coordinate	psi_degree
1053	IR Tracc 2nd Thorax rib Rotation	z-coordinate	psi_degree
1054	IR Tracc 3rd Thorax rib Rotation	z-coordinate	psi_degree
1055	IR Tracc 1st Abdomen rib Rotation	z-coordinate	psi_degree
1056	IR Tracc 2nd Abdomen rib Rotation	z-coordinate	psi_degree


Pelvis bone is separated into small parts for evaluations over
* CONTACT_FORCE_TRANSDUCER_PENALTY_ID, output data: rcforc



*C_F_T_P_ID 1043 *C_1

The * CONTACT_FORCE_TRANSDUCER_PENALTY_ID list:

Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1040	pelvis bone force left -	global contact force
		upper front	x-,y-,z-, resultant ;
Pelvis Force	1041	pelvis bone force left -	global contact force
		lower front	x-,y-,z-, resultant ;
Pelvis Force	1042	pelvis bone force left -	global contact force
		upper side forward	x-,y-,z-, resultant ;
Pelvis Force	1043	pelvis bone force left -	global contact force
		lower side forward	x-,y-,z-, resultant ;
Pelvis Force	1044	pelvis bone force left -	global contact force
		upper side middle	x-,y-,z-, resultant ;
Pelvis Force	1045	pelvis bone force left -	global contact force
		lower side middle	x-,y-,z-, resultant ;
Pelvis Force	1046	pelvis bone force left -	global contact force
		upper side rear	x-,y-,z-, resultant ;
Pelvis Force	1047	pelvis bone force left -	global contact force
		lower side rear	x-,y-,z-, resultant ;
Pelvis Force	1048	pelvis bone force left -	global contact force
		connection plate -	x-,y-,z-, resultant ;
		upper	
Pelvis Force	1049	pelvis bone force left -	global contact force
		connection plate -	x-,y-,z-, resultant ;
		lower	



5.4 Release notes of WorldSID v4.0

- Geometric modifications to the latest ISO hardware state (SBL-E):
 - $\circ~$ Geometric update of neck bracket and can be adjusted also in positioning simulation.



• Update of 2D IR-TRACC geometry. Due to this the physical stop angles are captured much more accurate.



 Battery in thorax has been changed to some smaller mass replacements





- Other modifications:
 - Arm validation is improved. In some Rib component test it is observer that WSID v3.5 seems to have a very soft arm behavior in bending. Due to this the behavior of the arm is compared to video evaluations and improved. In the following a rib component test with arm is shown for both versions of WorldSID:

10 ms

0

WSID v3.5



v4.0

10 ms





 For output of the EuroNCAP local rib deflections, DATABASE_HISTORY_NODE_LOCALS are defined. These nodes are included as an alternative to the output of the 2D IR-TRACCs. The nodes output the local x-, y- and z-deflection of the ribs. It must not be calculated from the resultant deflection and rotation of the 2D IR-TRACC.



Item	Node-	Label	Available components
	ID		
shoulder rib	10751	shoulder rib deformation Local X/Y/Z	x-, y-, z-displacement
1. thorax rib	10752	1 thorax rib deformation Local X/Y/Z	x-, y-, z-displacement
2. thorax rib	10753	2 thorax rib deformation Local X/Y/Z	x-, y-, z-displacement
3. thorax rib	10754	3 thorax rib deformation Local X/Y/Z	x-, y-, z-displacement
1. abdomen rib	10755	1 abdomen rib deformation Local X/Y/Z	x-, y-, z-displacement
2. abdomen rib	10756	2 abdomen rib deformation Local X/Y/Z	x-, y-, z-displacement

The nodes are:

- For dummy positioning the angles which are shown for Torso and Head are now global angles and no longer in respect to the Pelvis and Torso. So if the pelvis is rotated, they will also change. Due to this when the dummy is opened in Primer, two warning messages will occur that a coordinate systems does not belong to assembly 2 and 3.
- Positioning generator psg_v1.3 is improved. This is used to set up positioning pre simulations. Now it is possible also to rotate the neck backed by pre-simulation. This was missing in v3.5. Furthermore we switched the method to pulling the assemblies by esprings and dampers to the right position. This is very similar to the Primer method and very robust.
- The Version 4.0 and higher of the WorldSID provides parameters to scale the friction of the joint off all limbs. As default a 1 g adjustment of the joints is included. The user is now able to increase or decrease the friction values of the joints. The scale factors are used for the left and right hand side assemblies. So it is not possible to scale left and right assembly different.

Parameter name	Joint
sfarmx	Scale factor arms local x-rotation
sfarmy	Scale factor arms local y-rotation
sffemr	Scale factor upper legs all directions
sfknee	Scale factor knees
sfankl	Scale factor ankle joins all directions



5.5 Release notes of WorldSID v3.5

- Geometric modifications:
 - Initial Arm position is set to EuroNCAP position
 - EuroNCAP Oblique Pole Side Impact Testing Protocol (Version 7.0 of June 2014):
 - 5.3.6.1 Place both arms at the first detent downward of the most upward detent that corresponds to a differential angle of 32° between rib angle sensor and the arm angle.
 - Rib angle sensor is 0° if the 2. and 3. thorax ribs are horizontal.
 - Arm must then positioned 32° downwards from the horizontal.
 - Tree File is adjusted to show -32° for arm position.
 - Outer shape of V3.5 compared to V3.0 has not changed, except the Arm position.
 - One additional Node is generated NID10000. This one has the same coordinate as the node 10501 which is located on the H-Point.
 - This is pone due to positioning issues with the psg of the WolrdSID50.
- Other modifications:
 - $\circ~$ Due to a strange behavior of the Jacket in WSID v3.0 the Jacket is changed:
 - The solid material of the Jacket is improved.
 - The outer shell layer is changed from MAT-NULL to MAT_FABRIC with physical tension stiffness.

5.6 Release notes of WorldSID v3.0

- Geometric modifications:
 - The complete neoprene suit of the WorldSID is now meshed with solids
 - Arm foam and rubber mesh is disconnected from arm bone
 - 2D IR-TRACCs including new stop angles (SBL-E1)
 - New sacrum box data recorder in the pelvis (SBL-E1)
- Component modifications:
 - The arm component was improved
 - Neck model improvement
 - Shoulder rib component test in z-direction
- Other modifications:



- The nitinol material of the rib bands now uses am *MAT_SHAPE_MEMORY. This should increase the overall stability and robustness of the dummy model
- Some load cell orientations were corrected to match the SAE standard: upper and lower neck, shoulder, lumbar spine, pubic, sacro iliac and femur load cells
- Improvement of the pelvis flesh model to avoid high hourglass energies
- \circ $\,$ Improvement of the hole dummy definitions to reduce time step dependency of the model
- \circ $\,$ Parameter tpref to switch on/off the foam reference geometry of the thorax pad $\,$
- More robustness against variation of time step size
- New positioning procedure

5.7 Release notes of WorldSID v2.0

- The new sled tests are now validated in a first loop. So the interaction of different parts is adjusted and validated.
- First observations show very hard movement of the ribs in local zdirection. To investigate in this behavior there are planned new pendulum tests on the shoulder of the WorldSID.
- The validation of the single component tests of Version 1.0 is not changed. All single components of the WorldSID v2.0 are still the same.
- The WorldSID v2.0 fulfils still all available calibration tests.

5.8 Release notes of WorldSID v1.0

- The WorldSID model v1.0 is the first commercial available PDB WorldSID.
- The geometry and mass of the model are based on the data of ISO 15830 part 1 to 4.
- All important materials have been tested and used to generate corresponding material models.
- All available component tests are validated for the WorldSID v1.0
- The WorldSID v1.0 fulfills all available calibration tests.



6. Limitations and Further Work

The current release of the WorldSID has been validated by using material, component, dummy certification and sled tests. First experiences of full car simulations are included to the model.

The model is validated in use of the depicted tests in this Manual. The validation is done every time under physical aspects and in use of all know how which was available to this point in time.

For the next release, we are continue to improve the performance of the arm and thorax.

To carry on improving the model response and the usability we appreciate all users' feedback.



7. Material Tests

Material tests on all major foams, rubber like materials and plastics have been performed. The specimens were taken from components of the WorldSID or from blocks provided by FTSS. The material test samples are depicted below.



Figure 30: Material test samples of WorldSID

The following types of tests were performed: Static tension tests, dynamic tension tests, static compression tests, and dynamic compression tests. These tests were chosen to obtain material data that could be used with very small adaptations for material *MAT_FU_CHANG_FOAM and

*MAT_SIMPLIFIED_RUBBER for foam and rubber parts, respectively.

The following materials were tested:

- pelvis rubber foam
- upper arm rubber foam
- upper leg rubber
- lower leg rubber
- shoe rubber
- pubic rubber buffer
- Iumbar spine rubber
- all neck rubber materials (three different)

- vinyl (head skin)
- lower arm foam
- thorax pad foam (Ensolite)
- rib material (Nitinol)
- blue rib damping material
- plastics iliac wings
- arm bone
- head bone

The emphasis was on static and dynamic tension and compression tests. For the rubber like materials, the compression tests were also performed with a lateral obstructed expansion.



The strain rates used for the foam and rubber materials were:

Test	Туре	Strain rate	Lateral expansion
1	Tension	0.001 1/s (static)	free
2	Tension	0.1 1/s	free
3	Tension	20 1/s	free
4	Tension	100 1/s	free
5	Tension	400 1/s	free
6	Compression	0.001 1/s (static)	obstructed
7	Compression	0.001 1/s (static)	free
8	Compression	0.1 1/s	free
9	Compression	20 1/s	free
10	Compression	100 1/s	free
11	Compression	400 1/s	free

Table 40: Strain rates used for material tests



8. Performance

8.1 Component tests

Selected components of the WorldSID are tested in special defined component tests. The target of these tests is to have a fine validated component in a load range which can also be observed in a full car crash like the oblique pole of the FMVSS 214 new.

The tested components are:

- Head-neck unit
- Neck Torsion
- Half arm
- Arm Bending
- Arm Joint test
- Different ribs of the thorax and abdomen
- Lumbar spine
- Iliac wing

The description of the single component tests and the performance is given in the following chapters.

8.1.1 Head-neck test

This test is built to validate the neck unit in use of the mounted head assembly. The test setup is depicted in the figure below. The loads on the sled are defined to get signals which are similar to the neck signals in a full car crash.



Figure 31: Head-neck test setup - 90 degree, side and top view



The oblique plate is adapted only as a guide for the neck in the higher pulses. Two different pulses are tested for a 90 degree configuration as depicted in the previous figure and the same two pulses for a 75 degree configuration of the component. The configurations are listed in the table below.

Test	Load angle	Pulse
1	90 degree	20 g triangular pulse
2	90 degree	35 g triangular pulse
3	75 degree	20 g triangular pulse
4	75 degree	35 g triangular pulse

Table 41: Test configurations of head-neck test

Results of 90 degree, 20g configuration:



Figure 32: Result of head-neck test -- 20g, 90 degree (Head acceleration)









Lower neck load cell

Figure 34: Result of head-neck test -- 20g, 90 degree (Lower neck forces and moments)



Results of 90 degree, 35g configuration:



Figure 35: Result of head-neck test -- 35g, 90 degree (Head acceleration)



Figure 36: Result of head-neck test -- 35g, 90 degree (Upper neck forces and moments)





Figure 37: Result of head-neck test -- 35g, 90 degree (Lower neck forces and moments)





Results of 75 degree, 209 com

Figure 38: Result of head-neck test -- 20g, 75 degree (Head acceleration)





Figure 39: Result of head-neck test -- 20g, 75 degree (Upper neck forces and moments)



Figure 40: Result of head-neck test -- 20g, 75 degree (Lower neck forces and moments)



Results of 75 degree, 35g configuration:



Figure 41: Result of head-neck test -- 35g, 75 degree (Head acceleration)



Figure 42: Result of head-neck test -- 35g, 75 degree (Upper neck forces and moments)





Figure 43: Result of head-neck test -- 35g, 75 degree (Lower neck forces and moments)



8.1.2 Neck Torsion test

The neck is mounted on the test master-pendulum. The whole system get the velocity from master pendulum. There is a torsion pendulum which add an additional torsion to the neck.



Figure 44: Neck Torsion test setup with pendulum

The results of the test are shown in the following figure:





8.1.3 Half arm test

The arm is mounted on the test box using the original shoulder load cell. In most of the tests, the notch of the arm is in the 40 degree position. The load cell is then rotated so that the arm in each test is in a vertical position. For a different notch of the arm adjustment, only the shoulder load cell is rotated. The figure below shows the three pendulum positions used for the arm tests. In Table 42 all test setup configurations are listed.



Figure 46: Half arm test setup with all pendulum positions

Test	Shoulder load cell angle	Target point	Velocities
1	48 degree	А	2 m/s and 4 m/s
2	48 degree	В	2 m/s and 4 m/s
3	48 degree	С	2 m/s and 4 m/s
4	8 degree	В	2 m/s and 4 m/s
5	48 degree / middle bearing	В	4 m/s and 6 m/s
	modified		

Table 42: Test configurat	tions for half arm test
---------------------------	-------------------------

Test number 5 is done by using a reduced distance between the middle bearing and the arm. Target is that the arm hits the middle bearing after bending.



The results of all tests are shown in the following figures:



Results - Target point A, 4 m/s velocity, 48 degree load cell position





Figure 49: Results - Target point B, 2 m/s velocity, 48 degree load cell position



Figure 50: Results - Target point B, 4 m/s velocity, 48 degree load cell position



Figure 51: Results - Target point C, 2 m/s velocity, 48 degree load cell position



Figure 52: Results - Target point C, 4 m/s velocity, 48 degree load cell position



Figure 53: Results - Target point B, 2 m/s velocity, 8 degree load cell position



Figure 54: Results - Target point B, 4 m/s velocity, 8 degree load cell position





Results - Target point B, 4 m/s velocity, 48 degree load cell position and modified middle bearing

Figure 55: Results - Target point B, 4 m/s velocity, 48 degree load cell position, modified middle bearing

Results - Target point B, 6 m/s velocity, 48 degree load cell position and modified middle bearing



Figure 56: Results - Target point B, 6 m/s velocity, 48 degree load cell position, modified middle bearing



8.1.4 Arm Bending test

In order to validate the bending behavior of the half arm of WorldSID 50th, there are arm bending tests. Half arm with arm joint is mounted on a pendulum. There are two type of test: Arm joint in Y-direction is under 1g setting and fixed setting.



Figure 57: Arm bending test of WorldSID 50th



Figure 58: Results – 1g setting





Figure 59: Results - fixed setting

8.1.5 Arm Joint test

In order to validate the rotation behavior of the arm joint of WorldSID 50th, there are type of half arm pendulum tests: no additional force on arm joint, different additional force on arm joint.

No additional force on arm joint:



Figure 60: Arm joint test of WorldSID 50th, no additional force





Figure 61: Results – no additional force on arm joint, low velocity

Additional force on arm joint:



Figure 62: Arm joint test of WorldSID 50th, no additional force



Figure 63: Results – low additional force on arm joint, high velocity



Figure 64: Results - medium additional force on arm joint, low velocity





Figure 65: Results – medium additional force on arm joint, high velocity



Figure 66: Results – high additional force on arm joint, high velocity



8.1.6 Rib test

For the validation of the rib module of the WorldSID, many different tests have been performed. One single rib consists of two rib bands - an inner and an outer band. On the inner side of the inner band a blue damping material is tied. All ribs are built in a similar way. The difference in the shoulder, thorax and abdomen ribs are in the geometry and in the thickness of the damping material. The rib module is shown in the figure below:



Figure 67: Thorax construction of WorldSID

8.1.6.1 Inner rib band

The inner rib bands with damping material of the shoulder, the third thorax and second abdomen rib are tested. A pendulum test is performed with two different velocities on the single rib band as depicted below.

Shoulder rib:



Figure 68: Shoulder rib test on inner band with damping material





Figure 69: Shoulder rib test on inner band with damping material, low velocity



Figure 70: Shoulder rib test on inner band with damping material, high velocity



Third thorax rib:



Figure 71: Third thorax rib test on inner band with damping material



Figure 72: Shoulder rib test on inner band with damping material, low velocity





Figure 73: Shoulder rib test on inner band with damping material, high velocity



Second abdomen rib:

Figure 74: Second abdomen rib test on inner band with damping material.

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Figure 75: Second abdomen rib test on inner band with damping material, low velocity



Second abdomen rib inner band with damping material, high velocity IR-TRACC displ. x-displ. rib y-displ. rib

Figure 76: Second abdomen rib test on inner band with damping material, high velocity



8.1.6.2 Outer rib band

The outer rib band is tested in a similar way. A fully assembled thorax assembly is used and only the ribs above and below the tested rib are disassembled. The tested ribs are:

- Shoulder rib
- First thorax rib
- Third thorax rib
- Second abdomen rib

Each rib is tested with two velocities except the first thorax rib, where three different pendulum speeds are used.

The test is used to validate the behavior of the complete rib modules including the sternum materials.

Furthermore two different masses are used for the pendulum; hence there are four different test configurations for each single rib.

Shoulder rib:



Figure 77: Shoulder rib outer band test


Figure 78: Shoulder rib test on outer band - low velocity and low mass



Figure 79: Shoulder rib test on outer band - low velocity and high mass

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NA

time [ms]



Figure 80: Shoulder rib test on outer band - middle velocity and low mass

time [ms]



Figure 81: Shoulder rib test on outer band - middle velocity and high mass

time [ms]



Figure 82: Shoulder rib test on outer band - high velocity and low mass



Figure 83: Shoulder rib test on outer band - high velocity and high mass

NA



First thorax rib:



Figure 84: First thorax rib outer band test



Figure 85: First thorax rib test on outer band - low velocity and low mass



First thorax rib outer band - low velocity, high mass





Figure 87: First thorax rib test on outer band - middle velocity and low mass

NA





Figure 88: First thorax rib test on outer band - middle velocity and high mass



Figure 89: First thorax rib test on outer band - high velocity and low mass



Figure 90: First thorax rib test on outer band - high velocity and high mass

Third thorax rib:



Figure 91: Third thorax rib outer band test

NA



Figure 92: Third thorax rib test on outer band - low velocity and low mass



Figure 93: Third thorax rib test on outer band - low velocity and high mass

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Figure 94: Third thorax rib test on outer band - medium velocity and low mass



Figure 95: third thorax rib test on outer band - medium velocity and high mass





Figure 96: Third thorax rib test on outer band - high velocity and low mass



Figure 97: third thorax rib test on outer band - high velocity and high mass



Second abdomen rib:



Figure 98: Second abdomen rib outer band test



Figure 99: Second abdomen rib test on outer band - low velocity and low mass





Figure 100: Second abdomen rib test on outer band - low velocity and high mass



Figure 101: Second abdomen rib test on outer band - middle velocity and low mass





Figure 102: Second abdomen rib test on outer band - middle velocity and high mass



Figure 103: Second abdomen rib test on outer band - high velocity and low mass





Figure 104: Second abdomen rib test on outer band - high velocity and high mass



Additional second abdomen rib test:

Figure 105: Second abdomen rib additional test





Second abdomen rib additional - high velocity

Figure 106: Second abdomen rib test on outer band - high velocity and high mass



Figure 107: Second abdomen rib test on outer band - high velocity and high mass



8.1.6.3 Outer rib band vertical pendulum test

Since the release v3.5 there are additional test for the shoulder rib in vertical direction. With these tests the WorldSID model can be fine-tuned to capture the ribs vertical movement due to an impact.



Figure 108: shoulder rib tests in z-direction



Figure 109: shoulder rib test on outer band z-direction – low velocity





Figure 110: shoulder rib test on outer band z-direction – low velocity



Figure 111: shoulder rib test on outer band z-direction – medium velocity





Figure 112: shoulder rib test on outer band z-direction – medium velocity



Figure 113: shoulder rib test on outer band z-direction – high velocity





Figure 114: shoulder rib test on outer band z-direction – high velocity



8.1.6.4 Outer rib band with arm

Since the release v3.5 there are additional test for the shoulder rib with the assembled arm. These tests were performed with different pendulum velocities and two different impact angles.



Figure 115: shoulder rib tests with arm (90° on the right and 60° on the left)



Shoulder rib outer band with arm - low velocity, 90°

Figure 116: shoulder rib test on outer band with arm – low velocity, 90°





Figure 117: shoulder rib test on outer band with arm – low velocity, 90°



Shoulder rib outer band with arm - high velocity, 90°

Figure 118: shoulder rib test on outer band with arm - high velocity, 90°





Figure 119: shoulder rib test on outer band with arm - high velocity, 90°



Shoulder rib outer band with arm - low velocity, 60°

Figure 120: shoulder rib test on outer band with arm – low velocity, 60°





Figure 121: shoulder rib test on outer band with arm – low velocity, 60°



Shoulder rib outer band with arm - high velocity, 60°

Figure 122: shoulder rib test on outer band with arm - high velocity, 60°





Figure 123: shoulder rib test on outer band with arm - high velocity, 60°

8.1.6.5 Outer rib ban vertical pendulum test with arm

Since the release v3.5 there are additional test for the shoulder rib in oblique z-direction with assembled arm.



Figure 124: shoulder rib tests in oblique z-direction with arm







Figure 125: shoulder rib test oblique z-direction with arm – low velocity



Figure 126: shoulder rib test oblique z-direction - low velocity





Shoulder rib test oblique z-direction with arm - medium velocity



Figure 127: shoulder rib test oblique z-direction with arm – medium velocity



Figure 128: shoulder rib test oblique z-direction – medium velocity







Figure 129: shoulder rib test oblique z-direction with arm – high velocity



Figure 130: shoulder rib test oblique z-direction – high velocity



8.1.6.6 Additional Shoulder Rib test

Since the release v5.0 there are additional tests for the shoulder rib in different impact angle, Pendulum mass and impact Pendulum-velocity. Impact angle include 0, 90 and 180 degree. There is an impact box as half arm which is fixed on the arm joint. The test include two type, with sternum and without sternum. This is in order to identify the influence of the sternum. With these tests the WorldSID model can be fine-tuned to capture the rotation of shoulder rib by vertical axis.

0 Degree with sternum



Figure 131: Additional shoulder rib test, 0 degree with sternum



Figure 132: 0 Degree with sternum – low velocity





Figure 133: 0 Degree with sternum – low velocity



Figure 134: 0 Degree with sternum – low velocity



0 Degree with sternum, low pendulum mass - high velocity:







Figure 136: 0 Degree with sternum – high velocity





Figure 137: 0 Degree with sternum – high velocity

0 Degree without sternum



Figure 138: Additional shoulder rib test, 0 degree without sternum





0 Degree without sternum, low pendulum mass - low velocity:







Figure 140: 0 Degree without sternum - low velocity





Figure 141: 0 Degree without sternum - low velocity

0 Degree without sternum, low pendulum mass - high velocity:



Figure 142: 0 Degree without sternum – high velocity





Figure 143: 0 Degree without sternum - high velocity



Figure 144: 0 Degree without sternum - high velocity



90 Degree with sternum



Figure 145: Additional shoulder rib test, 90 degree with sternum



90 Degree with sternum, high pendulum mass - low velocity:

Figure 146: 90 Degree with sternum - low velocity





Figure 147: 90 Degree with sternum - low velocity



Figure 148: 90 Degree with sternum - low velocity


90 Degree with sternum, high pendulum mass - high velocity:







Figure 150: 90 Degree with sternum – high velocity





Figure 151: 90 Degree with sternum – high velocity

90 Degree without sternum



Figure 152: Additional shoulder rib test, 90 degree without sternum





90 Degree without sternum, high pendulum mass - low velocity:





Figure 154: 90 Degree without sternum – low velocity





Figure 155: 90 Degree without sternum - low velocity

90 Degree without sternum, high pendulum mass - high velocity:



Figure 156: 90 Degree without sternum - high velocity





Figure 157: 90 Degree without sternum – high velocity



Figure 158: 90 Degree without sternum – high velocity



180 Degree with sternum



Figure 159: Additional shoulder rib test, 180 degree with sternum



180 Degree with sternum, low pendulum mass - low velocity:

Figure 160: 180 Degree with sternum – low velocity





Figure 161: 180 Degree with sternum – low velocity



Figure 162: 180 Degree with sternum - low velocity



180 Degree with sternum, low pendulum mass - high velocity:







Figure 164: 180 Degree with sternum – high velocity





Figure 165: 180 Degree with sternum – high velocity

180 Degree without sternum



Figure 166: Additional shoulder rib test, 180 degree without sternum



180 Degree without sternum, low pendulum mass - low velocity:







Figure 168: 180 Degree without sternum - low velocity





Figure 169: 180 Degree without sternum – low velocity

180 Degree without sternum, low pendulum mass - high velocity:



Figure 170: 180 Degree without sternum – high velocity





Figure 171: 180 Degree without sternum – high velocity



Figure 172: 180 Degree without sternum - high velocity



8.1.7 Lumbar spine test

The lumbar spine component has also been validated by the use of a component test. Here, the sacrum block with adapted lumbar load cell and the lumbar spine itself is mounted on a sled. On the lumbar spine, a mass body is mounted, which should represent the load on the lumbar spine from the torso of the WorldSID. The test setup is depicted in the following picture.



Figure 173: Lumbar spine component test setup

The sled is loaded by the use of two different pulses (20g triangular and 35g triangular) and the orientation of the lumbar spine is made for each pulse -- 90 and 60 degree. The test configurations are listed in the Table 43.

Test	Load angle	Pulse	
1	90 degree	20 g triangular pulse	
2	90 degree	35 g triangular pulse	
3	60 degree	20 g triangular pulse	
4	60 degree	35 g triangular pulse	

 Table 43: Test configurations for lumbar spine test



Results of 90 degree, 20g configuration:



Figure 174: Result of lumbar spine test -- 20g, 90 degree (Mass body accelerations)



Figure 175: Result of lumbar spine test -- 20g, 90 degree (Lumbar load cell forces and moments)





Figure 176: Result of lumbar spine test -- 20g, 90 degree (Mass body rotations)



Results of 90 degree, 35g configuration:

Figure 177: Result of lumbar spine test -- 35g, 90 degree (Mass body accelerations)





Figure 178: Result of lumbar spine test -- 35g, 90 degree (Lumbar load cell forces and moments)



Figure 179: Result of lumbar spine test -- 35g, 90 degree (Mass body rotations)



Results of 60 degree, 20g configuration:



Figure 180: Result of lumbar spine test -- 20g, 60 degree (Mass body accelerations)



Figure 181: Result of lumbar spine test -- 20g, 60 degree (Lumbar load cell forces and moments)





Figure 182: Result of lumbar spine test -- 20g, 60 degree (Mass body rotations)



Results of 60 degree, 35g configuration:

Figure 183: Result of lumbar spine test -- 35g, 60 degree (Mass body accelerations)





Figure 184: Result of lumbar spine test -- 35g, 60 degree (Lumbar load cell forces and moments)



Figure 185: Result of lumbar spine test -- 35g, 60 degree (Mass body rotations)



8.1.8 Iliac wing test

The iliac wings are tested in three different configurations with the use of two different velocities. Here, the sacrum block with mounted iliac wings and pubic load cell is fixed on a table. The first two configurations use only one iliac wing and the half pubic construction. The third configuration is a load on the complete assembled pelvis area without the pelvis foam. The different configurations are depicted in the following figures.



Figure 186: Iliac wing component test configurations

Test	Target point	Test setup	Velocities
1	A	half pelvis	low and high velocity
2	В	half pelvis	low and high velocity
3	В	full pelvis	low and high velocity

Table 44: Test configurations for iliac wing test



Results of target point A, low velocity, half pelvis:



Figure 187: Result of iliac wing test -- Target point A, low velocity, half pelvis (Pendulum accelerations)



Figure 188: Result of iliac wing test -- Target point A, low velocity, half pelvis (Sacro-iliac load cell)



Results of target point A, high velocity, half pelvis:



Figure 189: Result of iliac wing test -- Target point A, high velocity, half pelvis (Pendulum accelerations)







Results of target point B, low velocity, half pelvis:



Figure 191: Result of iliac wing test -- Target point B, low velocity, half pelvis (Pendulum accelerations)



Figure 192: Result of iliac wing test -- Target point B, low velocity, half pelvis (Sacro-iliac load cell)







Figure 193: Result of iliac wing test -- Target point B, high velocity, half pelvis (Pendulum accelerations)



Figure 194: Result of iliac wing test -- Target point B, high velocity, half pelvis (Sacro-iliac load cell)



Results of target point B, low velocity, full pelvis:



Figure 195: Result of iliac wing test -- Target point B, low velocity, full pelvis (Pendulum accelerations)



Figure 196: Result of iliac wing test -- Target point B, low velocity, full pelvis (Sacro-iliac load cell)



Results of target point B, high velocity, full pelvis:



Figure 197: Result of iliac wing test -- Target point B, high velocity, full pelvis (Pendulum accelerations)







8.2 Calibration tests

The calibration tests are also used to validate the WorldSID model. The tests are used as described in the WorldSID manual of the physical dummy (Road vehicles — Design and performance specifications for the WorldSID 50th percentile male side-impact dummy, Part 1-4, ISO 15830-1 to 15830-4).

For each test, a short description of the test configuration is given in each single section. For more detailed information of the test setup please use the hardware manual of the WorldSID.

8.2.1 Head drop test

The disconnected head drops on a rigid plate. Then the head accelerations are measured.

Two configurations are used: frontal and lateral drop test. The configurations are depicted in the following figure.



Figure 199: Head drop test, Left: Frontal test, Right: Lateral test

The results and the corridors are shown in the following 2 plots:



Figure 200: Results of frontal head drop test



Figure 201: Results of lateral head drop test





8.2.2 Neck pendulum test

The neck calibration test is simulated as described in the WorldSID manual ISO-15830 part 2. The test setup is depicted in the figure below. The neck is adapted to a long pendulum. The pendulum runs into a part of honeycomb to get decelerated, thereby causing the neck to bend against the load direction. As mass replacement, the head form is used instead of the original head.



Figure 202: Neck pendulum calibration test setup

In the test, the load cell forces and moments are measured and the rotations of the points A and B are used to describe the kinematics of the neck.

The results and the corresponding calibration corridors are shown in the following figures.



NA



Figure 203: Result of neck calibration test upper neck load cell



Figure 204: Result of neck calibration test head form rotations



8.2.3 Shoulder pendulum test



Figure 205: Shoulder calibration test setup



Figure 206: Shoulder calibration test results with arm (Page 1)



8.2.4 Thorax pendulum test without arm



Figure 207: Thorax calibration test setup without arm

Results of thorax calibration test without arm (Page 1)





Results of thorax calibration test without arm (Page 2)



Since WorldSID50th version 5.00 there is parameter &trd_opt which can choice the thickness of the thorax damping material. The effect of &trd_opt for thorax calibration is shown below:

Results of thorax calibration test without arm with trd_opt effect (P 1)



Figure 210: Thorax calibration test results without arm with trd_opt effect (P 1)

ΝΔ





Results of thorax calibration test without armwith trd_opt effect (P 2)1. thorax rib intrusion SAE 6002. thorax rib intruson SAE 600

Figure 211: Thorax calibration test results without arm with trd_opt effect (P 2)



8.2.5 Thorax pendulum test with arm



Figure 212: Thorax calibration test setup with arm

Results of thorax calibration test with arm (Page 1)







Results of thorax calibration test with arm (Page 2)


8.2.6 Abdomen pendulum test



Figure 215: Abdomen calibration test setup

Results of abdomen calibration test with arm (Page 1)





8.2.7 Pelvis pendulum test



Figure 217: Pelvis calibration test setup

Results of pelvis calibration test with arm (Page 1)





8.3 Sled Tests

The following sled tests are used for validation. There are two different sled shapes and for each shape two different arm positions. In addition one test is done without the jacket and one without the Arm.



Figure 219: Sled tests for next WorldSID release. Left hand side: Plane sled. Right hand side: Plane sled with pelvis pusher



8.3.1 Flat barrier

8.3.1.1 Arm position second notch



Figure 220: Flat barrier and arm second notch.



Low velocity:































8.3.1.2 Arm position first notch



Figure 221: Flat barrier and arm first notch.



Low velocities:































8.3.2 Pelvis shape barrier

8.3.2.1 Arm position second notch



Figure 222: Pelvis barrier and arm second notch.



Low velocity:















8.3.2.2 Arm position first notch



Figure 223: Pelvis barrier and arm first notch.



Low velocity:































8.3.3 Flat barrier and WorldSID without arm



Figure 224: Flat barrier and without arm.

















8.3.4 Pelvis shape barrier and WorldSID without Jacket

Figure 225: Pelvis barrier and arm first notch without jacket.


















9. Literature

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