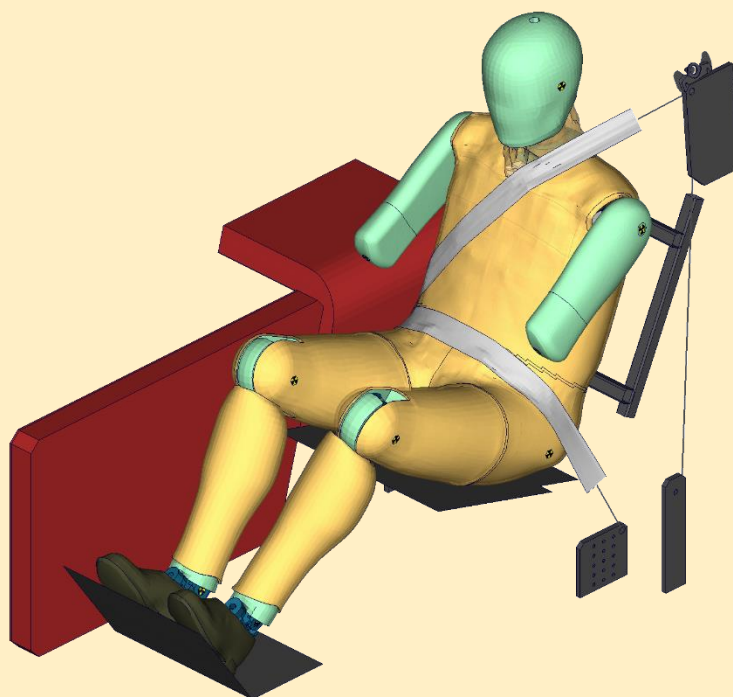


Documentation

PDB LS-DYNA

WorldSID 50th – Version 8.0



User's Manual

Manual Release for Model v8.0
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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.
R9.3 MPP	03/13/2021	618-gee79cb9
R11 MPP	07/02/2020	2736-g41bc835
R12 MPP	08/02/2022	4134-g382192fb50
R14 MPP	08/22/2022	250-ge61a75b799

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 calibration and barrier sled tests:

LS-DYNA Version	Date	Revision Nr.	recommended
R9.3 MPP	03/13/2021	618-gee79cb9	yes
R11 MPP	07/02/2020	2736-g41bc835	yes
R12 MPP	08/02/2022	4134-g382192fb50	yes
R14 MPP	08/22/2022	250-ge61a75b799	yes

Table 2: recommended LS-DYNA versions

With the version 8.0 of the WorldSID 50th model the following keyword files are delivered:

File name	Content
worldSID50_pdb_v8.0_mm_ms_kg.key	Dummy model; the file name might vary depending on the system of units
worldSID50_pdb_v8.0_mm_ms_kg_IR-TRACC_left.key	IR-TRACC LHD include file; the file name might vary depending on the system of units
worldSID50_pdb_v8.0_mm_ms_kg_IR-TRACC_right.key	IR-TRACC RHD include file; the file name might vary depending on the system of units
worldSID50_pdb_v8.0_Ballast_left.key	Ballast LHD include file
worldSID50_pdb_v8.0_Ballast_right.key	Ballast RHD include file
Psg_v2.2_...	Script to generate pre-simulation input (chapter 3.2).
wsid50_v8.0_all_units_server.asc	License file; the file can be used in different system of units
wsid50_v8.0_all_units_load_curves_work.key	Work file used for pre-processing instead of license file. The file name

worldSID50_pdb_v8.0_H-Point_tool.key	might vary depending on the system of units H-Point measurement device
worldSID50_pdb_v8.0_mm_ms_kg_RibEye_left.key	RibEye LHD model; the file name might vary depending on the system of units
worldSID50_pdb_v8.0_mm_ms_kg_RibEye_right.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 LHD and RHD model (Do not include RibEye model and H-Point model, for RibEye model details please check the RibEye model user manual) is shown separately.

On request, we deliver renumbered input decks, according to user specifications.

Component LHD	Min ID	Max ID	Total number
Nodes	10000	787563	592721
Solids	480396	946029	450568
Beams	10000	11671	783
Shells	12001	355975	298710
Element Mass	10001	10002	2
Discrete elements	10030	10086	38
Accelerometer	1001	1023	22
Set node	1003	33563	12980
Set shell	1029	1029	1
Set parts	1001	1582	46
Parts	1	999	941
Materials	1001	1139	128
Sections	1003	1113	99
Hourglass	1001	1010	6
Airbags	1	2	2
Airbag reference geometry	1	1	1
Joints	1024	1024	1
Joint stiffness	1001	1075	39
Nodal rigid bodies	10024	33563	12960
Contacts	1001	1069	26
Local coordinate systems	1001	1096	93

General Information

Load curves / tables	1001	1149	121
Define SD orientation	1001	1120	32
Time history nodes	10001	10776	49
Time history beam elements	10000	10256	22
Time history discrete elements	10030	10086	32
Component RHD	Min ID	Max ID	Total number
Nodes	10000	787563	592721
Solids	480396	956029	450568
Beams	10000	11918	783
Shells	12001	355975	298710
Element Mass	10001	10002	2
Discrete elements	10030	10365	38
Accelerometer	1001	1023	22
Set node	1003	33563	12980
Set shell	1029	1029	1
Set parts	1001	1570	46
Parts	1	999	941
Materials	1001	1139	128
Sections	1003	1113	99
Hourglass	1001	1010	6
Airbags	1	2	2
Airbag reference geometry	1	1	1
Joints	1024	1024	1
Joint stiffness	1001	1081	39
Nodal rigid bodies	10024	33563	12960
Contacts	1001	1069	26
Local coordinate systems	1001	1296	93
Load curves / tables	1001	1149	121
Define SD orientation	1001	1120	32
Time history nodes	10001	10355	49
Time history beam elements	10000	10256	22
Time history discrete elements	10030	10365	32

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_HOURLASS
*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_BEAM	*MAT_SIMPLIFIED_RUBBER
*MAT_NONLINEAR_ELASTIC_DISCRETE_BEAM	*MAT_SIMPLIFIED_RUBBER_WITH_DAMAGE
*MAT_NULL	*MAT_SPRING_ELASTIC
*MAT_PLASTIC_KINEMATIC	*MAT_SPRING_NONLINEAR_ELASTIC
	*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	*HOURLASS
*CONSTRAINED_JOINT_SPHERICAL_ID	*INCLUDE

Used Keyword

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

Table 8: Other keywords used in the model

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

*ASSEMBLY *CONNECTION_HINGE *CONNECTION_LINE *DUMMY_END *DUMMY_START *H_POINT	*MECHANISM_START *MECHANISM_END *POINT_LOCATION *POSITION *UNITS
--	--

Table 9: Primer keywords used

1.2 Mass Measurements

The follow table shows current mass measurements between ISO 15830-2 specification masses (2022) und WSID 50th Model version 8.0:

Item	Hardware Mass [kg]	Hardware +/- [kg]	ISO 15830-2 Range [kg]		Model Mass [kg]
Head	4.29	0.05	4.24	4.34	4.29
Neck	2.86	0.02	2.84	2.88	2.86
Thorax/abdomen/shoulder	20.56	0.35	20.21	20.91	20.56
Lower Torso	19.30	0.20	19.10	19.50	19.30
Two half Arms	3.52	0.08	3.44	3.60	3.52
Two Upper Legs	11.72	0.08	11.64	11.80	11.72
Two Lower Legs	10.12	0.14	9.98	10.26	10.12
Clothing	1.62	0.16	1.46	1.78	1.62
Total	73.99	1.08	72.91	75.07	73.99

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.

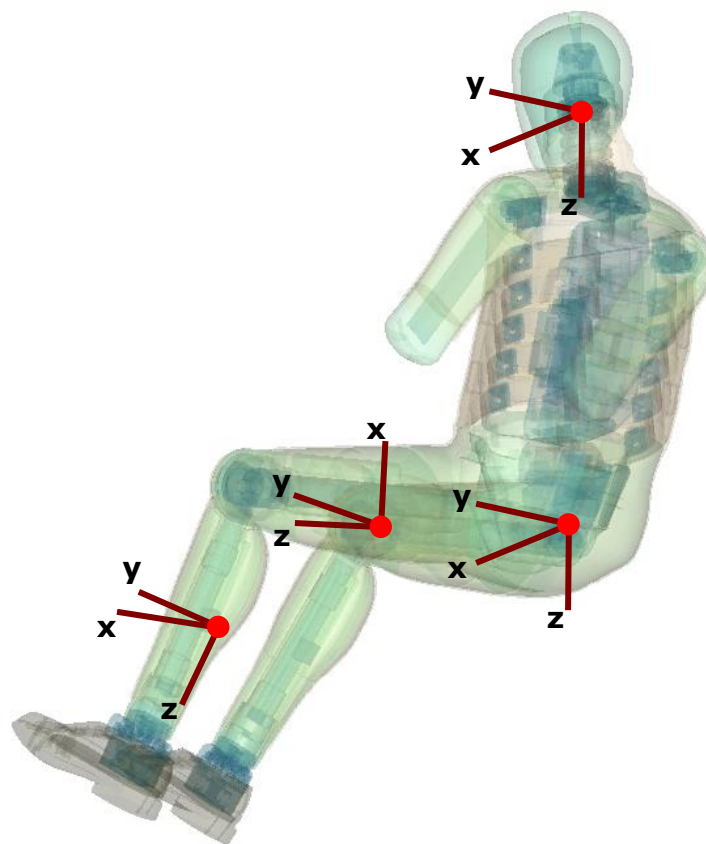


Figure 1: Orientation of the coordinate systems for accelerometers and load cells in the WORLD SID 50th model

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

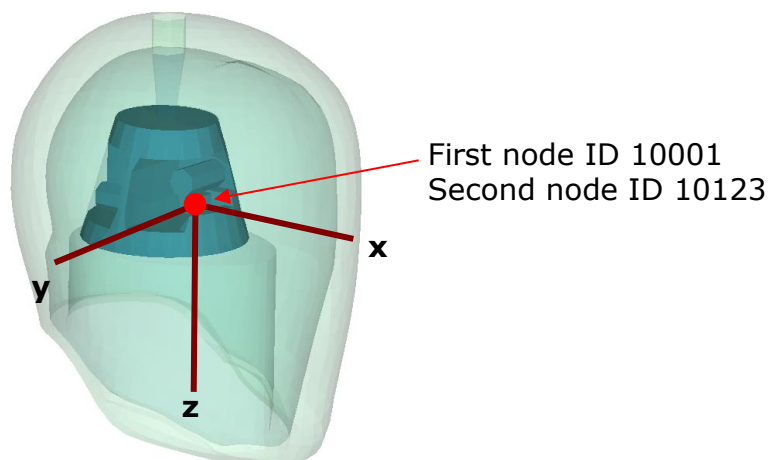


Figure 2: Head accelerometer and local coordinate directions

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

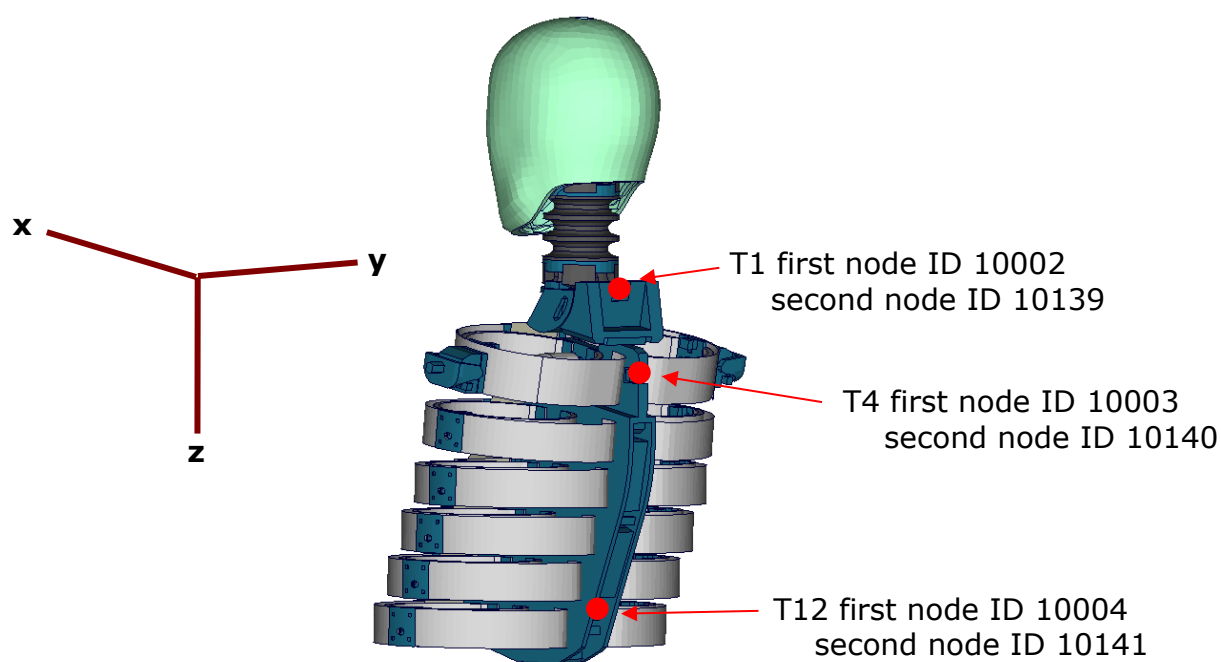


Figure 3: T1, T4 and T12 accelerometer nodes

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

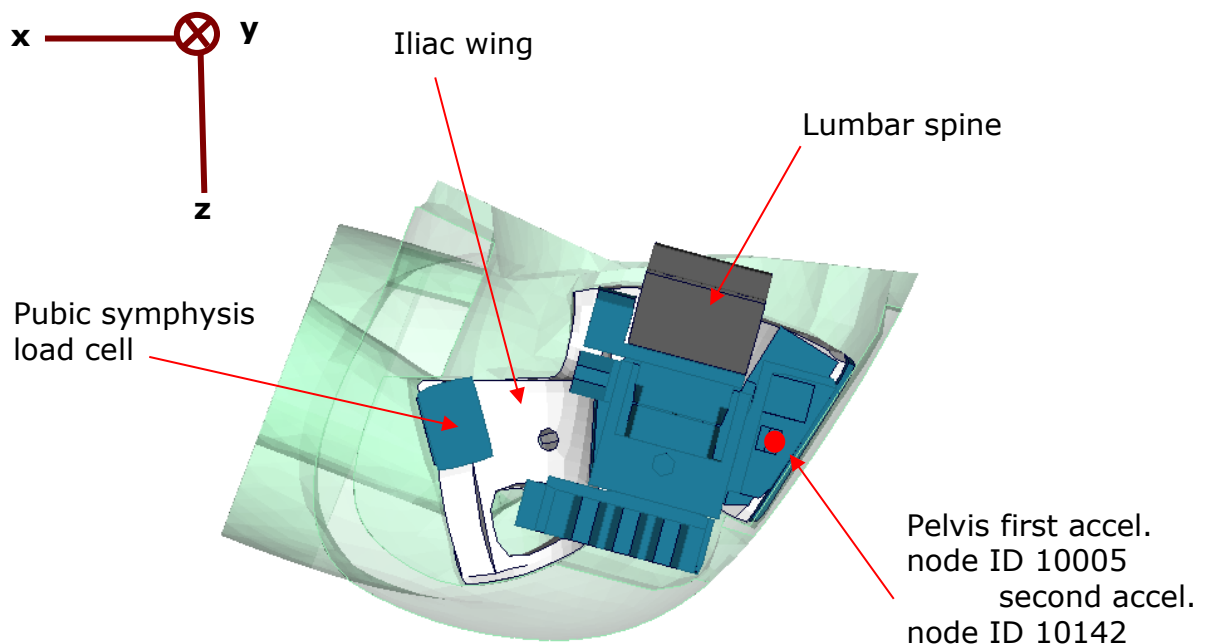


Figure 4: Node to extract pelvis acceleration.

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.

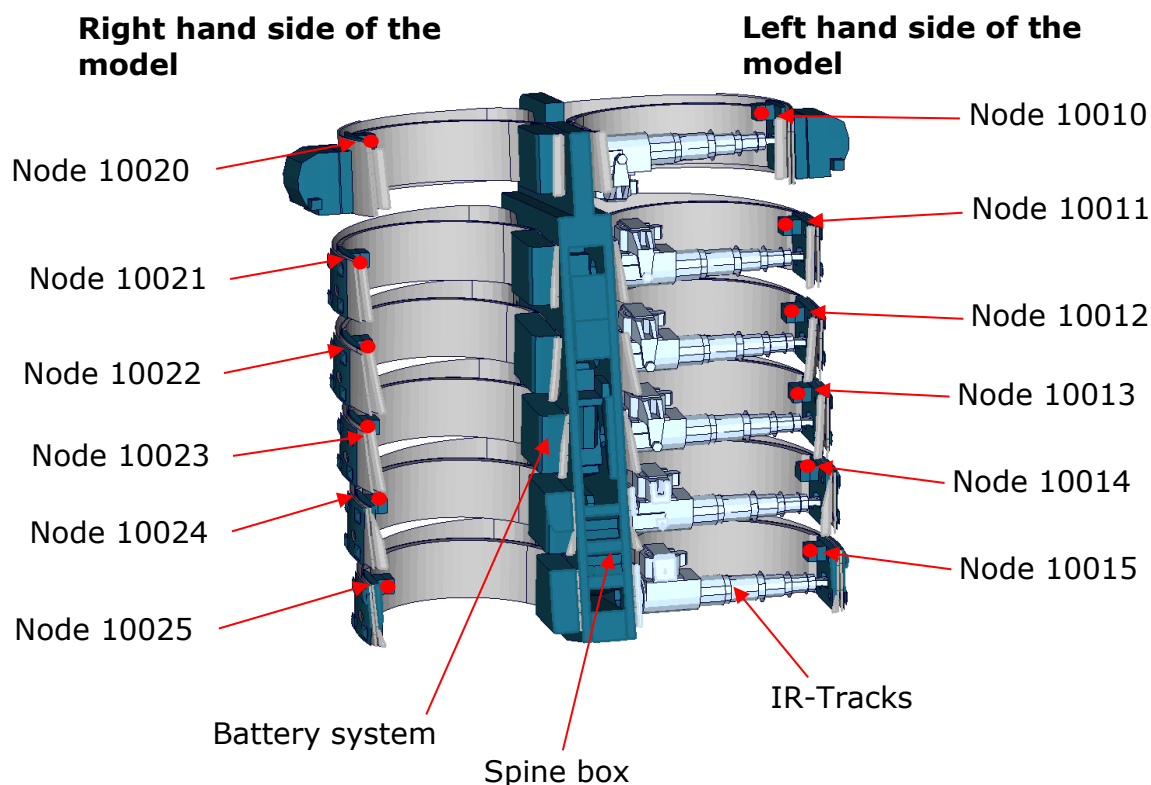


Figure 5: Cut through upper torso and position of rib accelerometer nodes

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
3. 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.

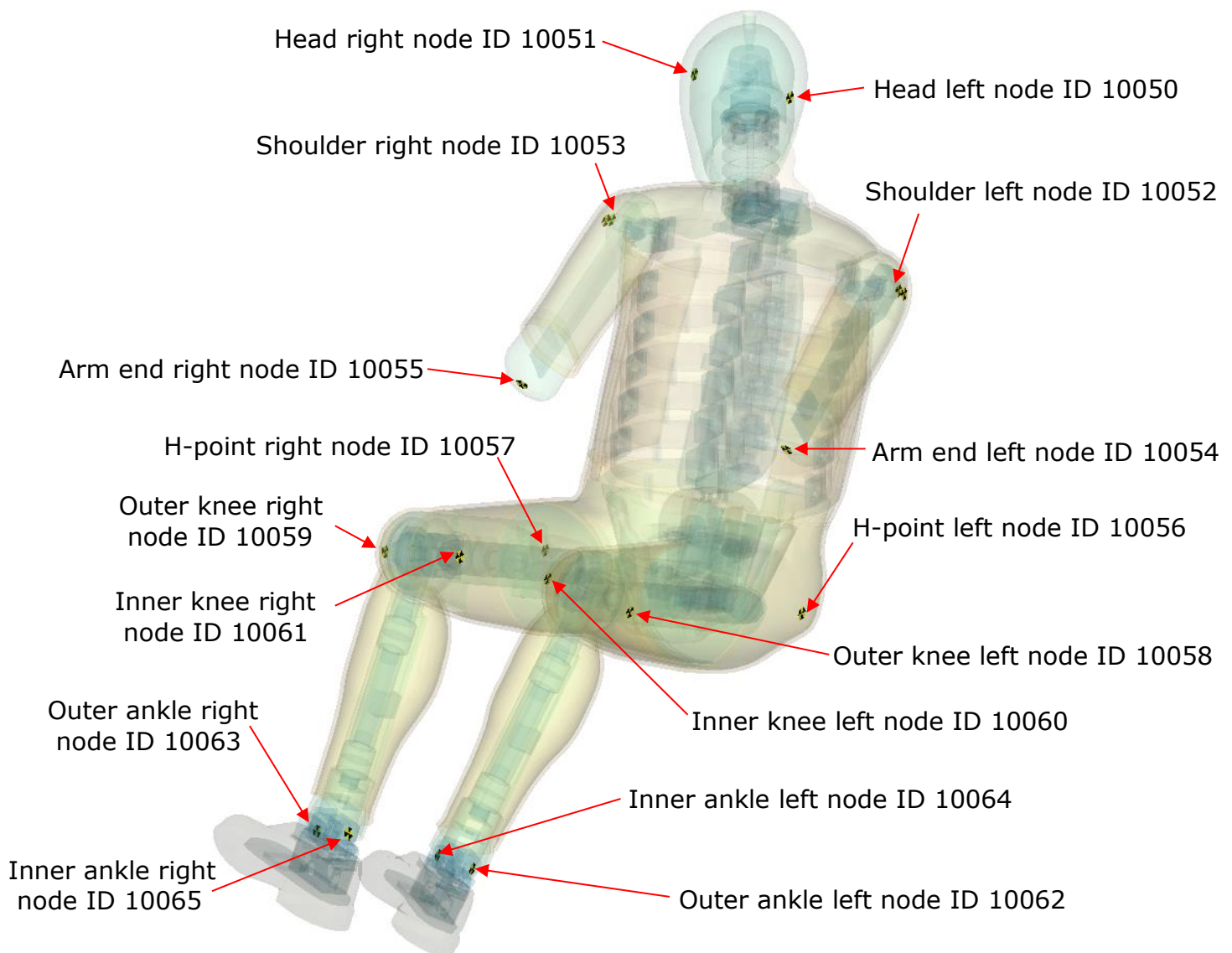


Figure 6: Nodes for evaluation of marker

Extraction of occupant injury criteria

The nodes' list is:

Item	Node-ID	Label	Available components
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	ARM0LEMAWSAC	global node output
marker arm end right	10055	ARM0RIMAWSAC	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 right	10065	ANKLRIMIWSAC	global node output

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. The directions are the ELOUT file output direction, not the local coordinate system.

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 ELOUT file for evaluating load cell results

2.3.1 Upper and lower neck load cell

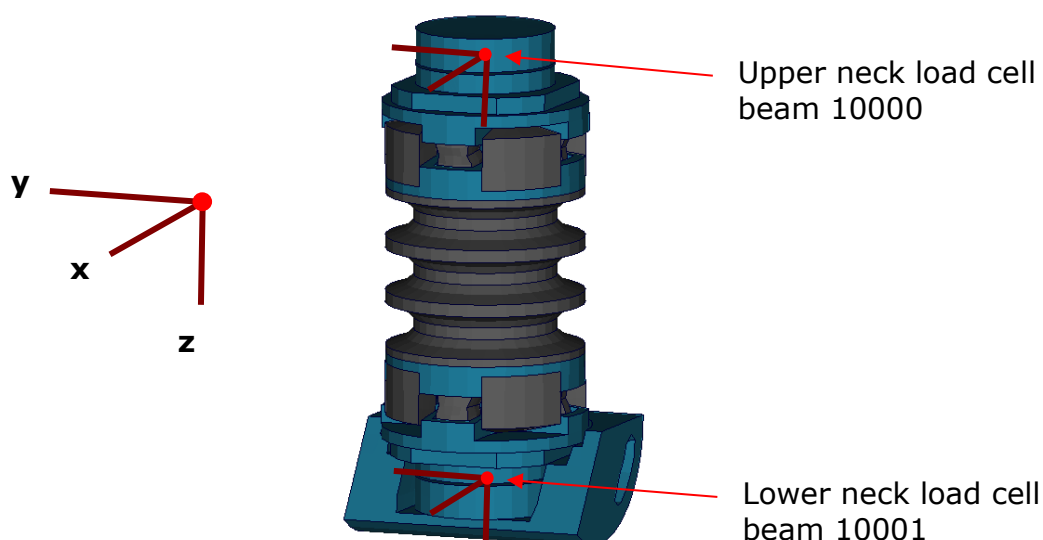


Figure 7: Upper and lower neck load cells

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.

For Positive upper and lower load cell output per SAE J-211:

- +FX: Head rearward, Chest forward
- +FY: Head leftward, Chest rightward
- +Fz: Head upward, Chest downward
- +MX: Left ear toward left shoulder
- +MY: Chin toward sternum
- +MZ: Chin toward left shoulder

2.3.2 Shoulder load cell left and right

Shoulder load cell
right beam 10003

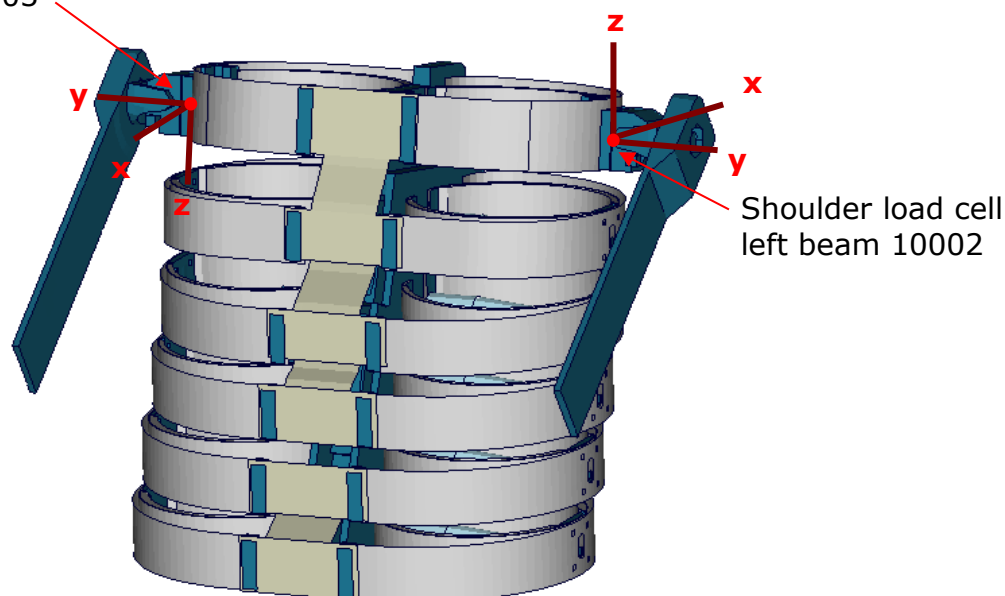


Figure 8: Shoulder load cells, left and right.

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.

For Positive shoulder load cell output per SAE J-211:

Left-side load cell

- +FX: Arm rearward, hold torso in place
- +FY: Arm leftward, hold torso in place
- +Fz: Arm upward, hold torso in place

Right-side load cell

- +FX: Arm forward, hold torso in place
- +FY: Arm rightward, hold torso in place
- +Fz: Arm downward, hold torso in place

2.3.3 Lumbar load cell

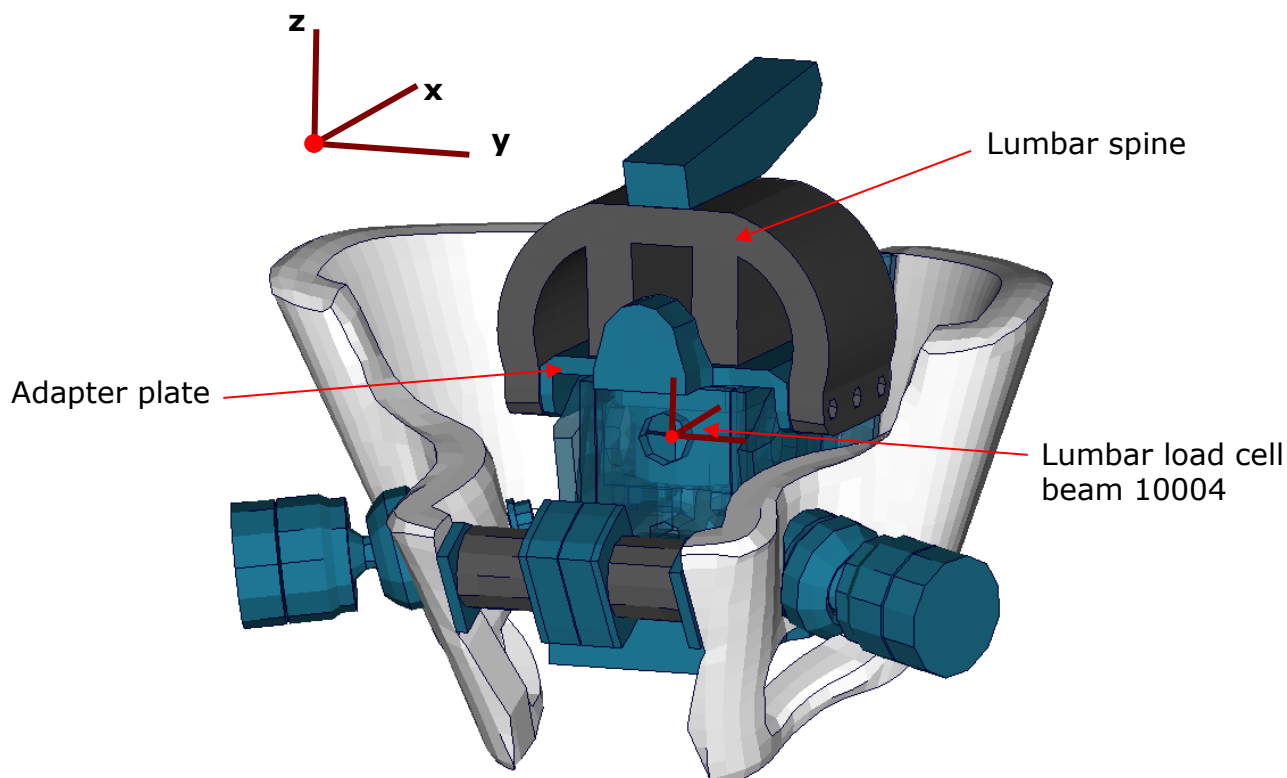


Figure 9: Lumbar load cell in Sacrum block

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.

For Positive lumbar load cell output per SAE J-211:

- +FX: Chest rearward, Pelvis forward
- +FY: Chest leftward, Pelvis rightward
- +Fz: Chest upward, Pelvis downward

- +MX: Left shoulder toward left hip
- +MY: Sternum toward front of legs
- +MZ: Right shoulder forward, Left shoulder rearward

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.

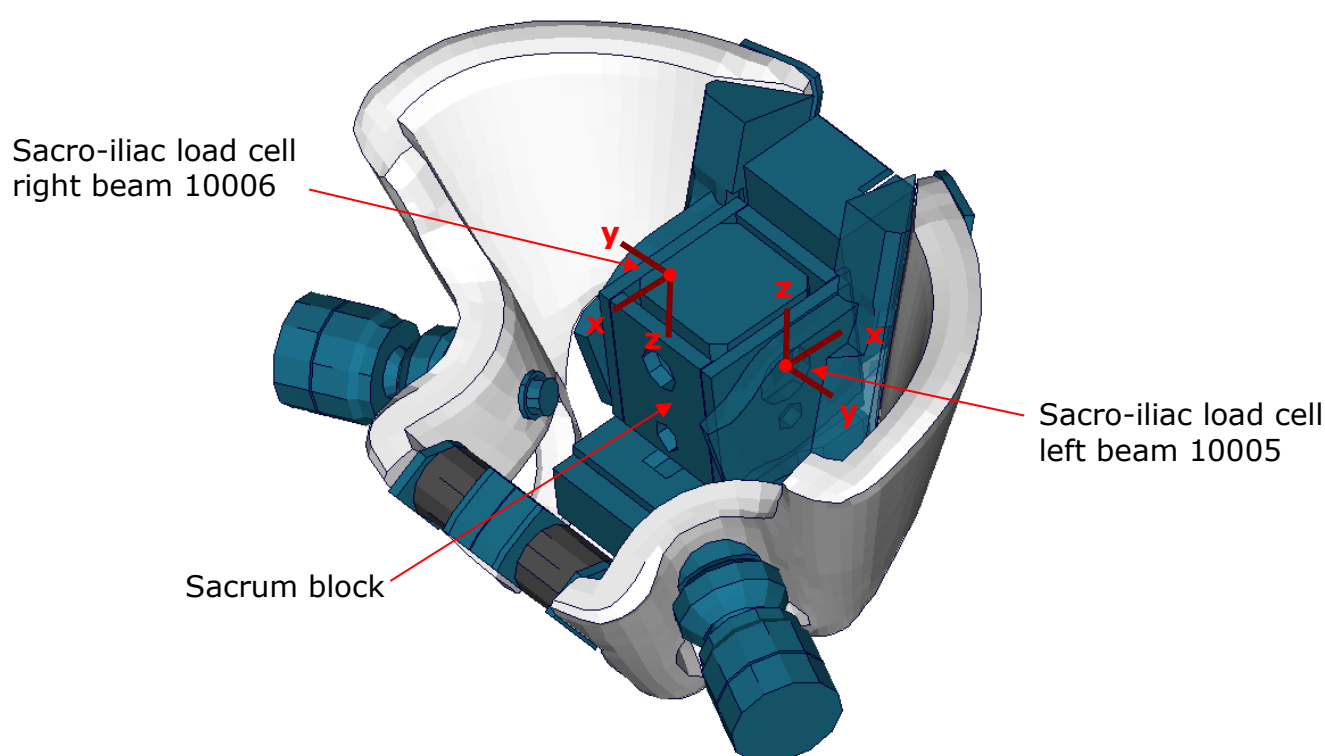


Figure 10: Sacro-iliac load cells, left and right hand side

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.

For Positive sacro-iliac load cell output per SAE J-211:

Left-side sacro-iliac load cell

- +FX: Left iliac wing rearward, Lumbar forward
- +FY: Left iliac wing leftward, Lumbar rightward
- +FZ: Left iliac wing upward, Lumbar downward
- +MX: Push downward on top edge of left iliac wing, hold lumbar in place
- +MY: Push downward on left pubic interface, hold lumbar in place
- +MZ: Push leftward on left pubic interface, hold lumbar in place

Right-side sacro-iliac load cell

- +FX: Right iliac wing forward, Lumbar rearward
- +FY: Right iliac wing rightward, Lumbar leftward
- +FZ: Right iliac wing downward, Lumbar upward
- +MX: Push downward on top edge of right iliac wing, hold lumbar in place
- +MY: Push upward on right pubic interface, hold lumbar in place
- +MZ: Push rightward on right pubic interface, hold lumbar in place

2.3.5 Pubic symphysis load cell

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

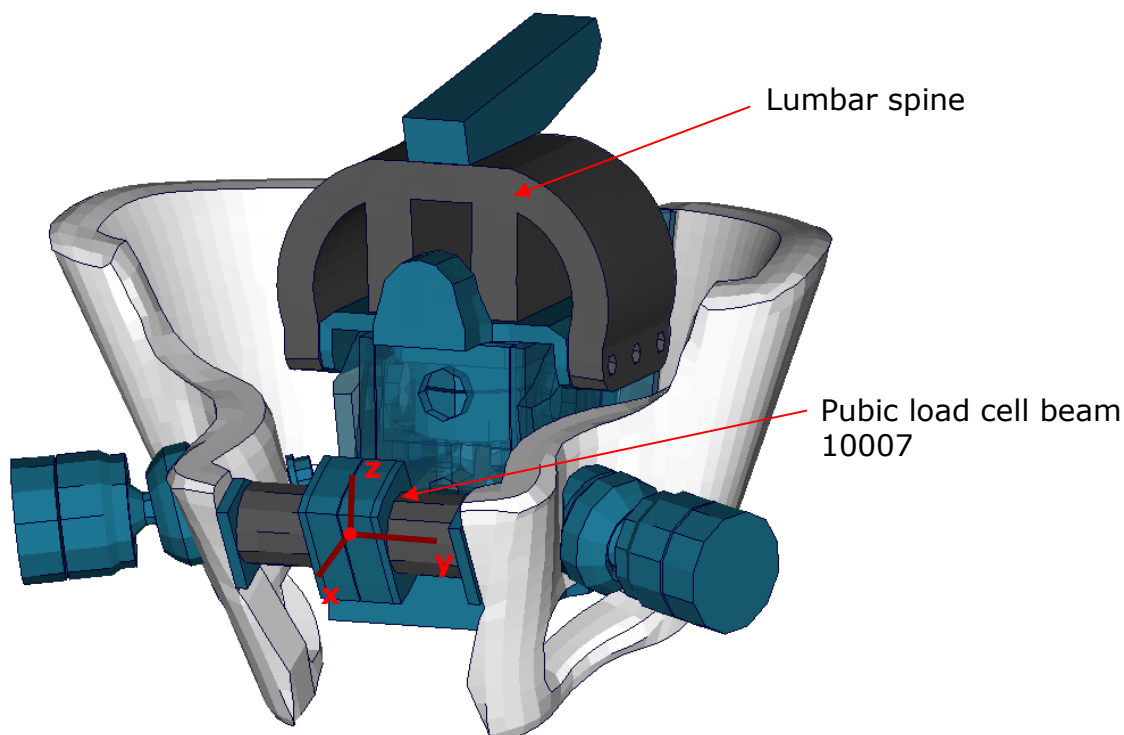


Figure 11: Pubic load cell adapted to pelvis bones

For Positive pubic load cell output per SAE J-211:

Pubic load cell

+FX: Right iliac wing forward, Left iliac wing rearward

+FY: Right iliac wing rightward, Left iliac wing leftward

+FZ: Right iliac wing downward, Left iliac wing upward

+MX: Push downward on the right side of the pubic load cell, hold left iliac wing in place

+MY: Twist right side of pubic load cell counterclockwise when viewed from right side of load cell, hold left iliac wing in place

+MZ: Push rearward on right side of pubic load cell, hold left iliac wing in place

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:

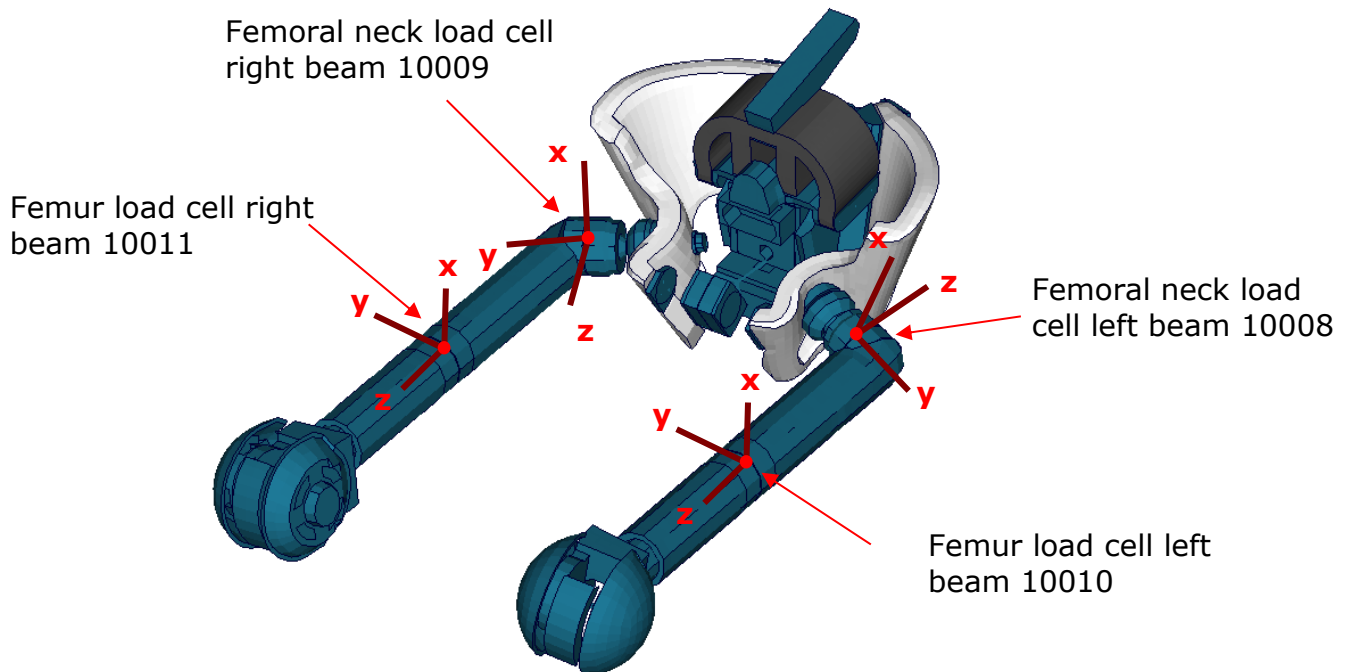


Figure 12: Upper and lower femur load cells

For Positive femoral neck load cell output per SAE J-211:

Right femoral neck load cell

+FX: Right femur upward, pelvis downward

+FY: Right femur rightward, pelvis leftward

+FZ: Right femur forward, pelvis rearward

Left femoral neck load cell

+FX: Left femur downward, pelvis upward

+FY: Left femur leftward, pelvis rightward

+FZ: Left femur rearward, pelvis forward

For Positive femur load cell output per SAE J-211:

Femur load cell

+FX: Knee upward, trochanter downward

+FY: Knee rightward, trochanter leftward

+FZ: Knee forward, trochanter rearward

+MX: Knee leftward, hold trochanter in place

+MY: Knee upward, hold trochanter in place

+MZ: With tibia perpendicular to femur, rotate tibia leftward, hold pelvis in place

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

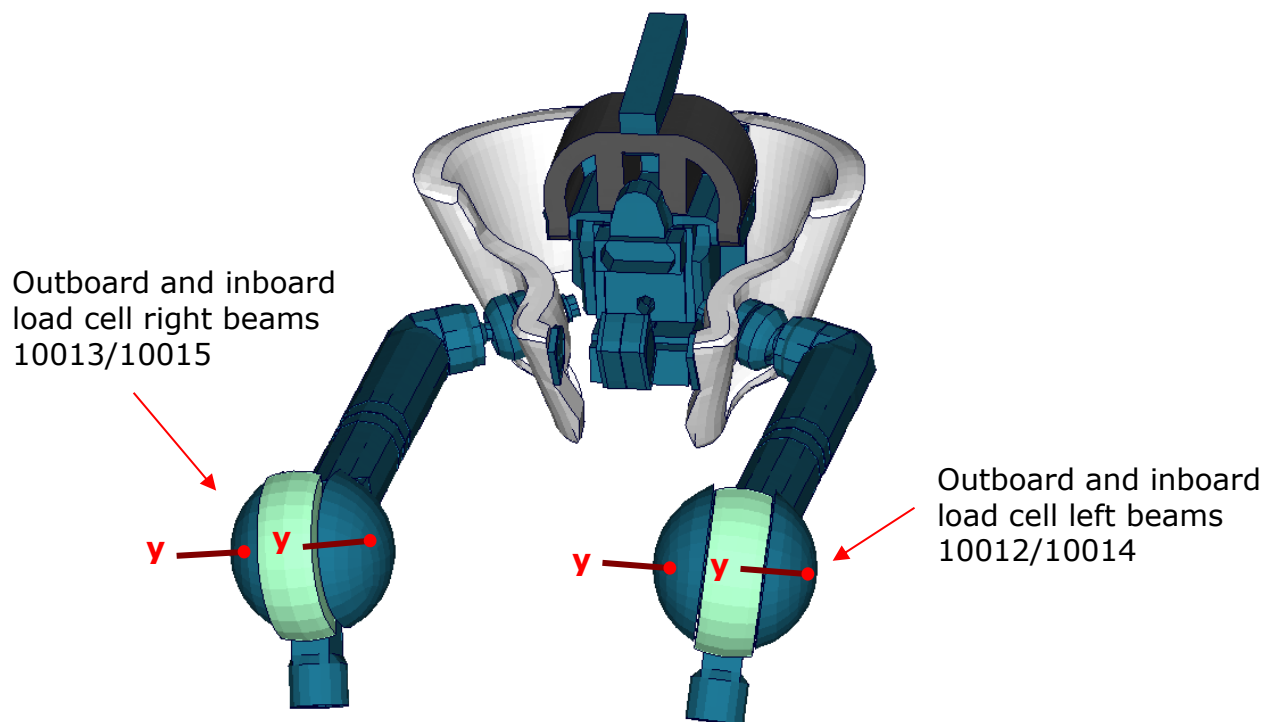


Figure 13: Knee load cell beams

For Positive knee load cell output per SAE J-211:

Left knee outboard side load cell

+FY: Push outboard side rightward, hold femur in place

Left knee inboard side load cell

-FY: Push inboard side leftward, hold femur in place

Right knee outboard side load cell

-FY: Push outboard side leftward, hold femur in place

Right knee inboard side load cell

+FY: Push inboard side rightward, hold femur in place

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

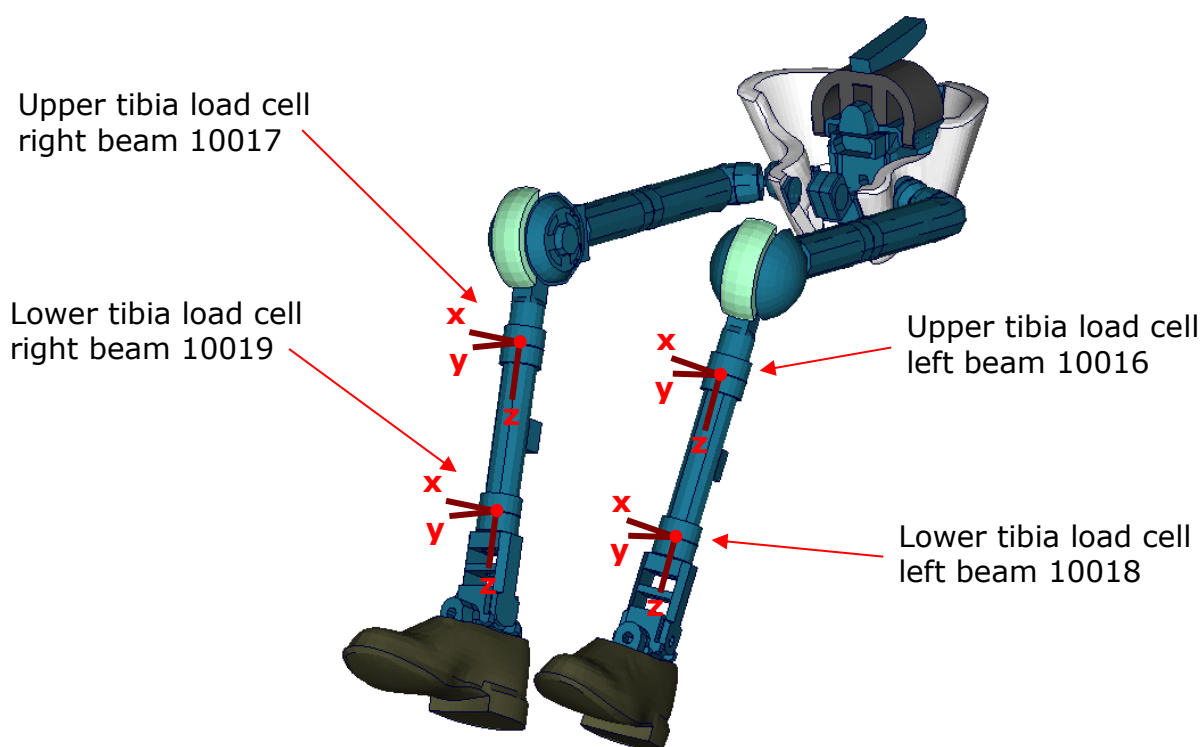


Figure 14: Tibia load cell beams

For Positive tibia load cell output per SAE J-211:

Upper tibia load cell

+FX: Tibia forward, knee rearward

+FY: Tibia rightward, knee leftward

+FZ: Tibia downward, knee upward

+MX: Tibia leftward, hold knee in place

+MY: Tibia forward, hold knee in place

+MZ: Rotate foot counterclockwise when viewed from bottom of shoe

Lower tibia load cell

+FX: Ankle forward, knee rearward

+FY: Ankle rightward, knee leftward

+FZ: Ankle downward, knee upward

+MX: Ankle leftward, hold knee in place

+MY: Ankle forward, hold knee in place

+MZ: Rotate foot counterclockwise when viewed from bottom of shoe

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.

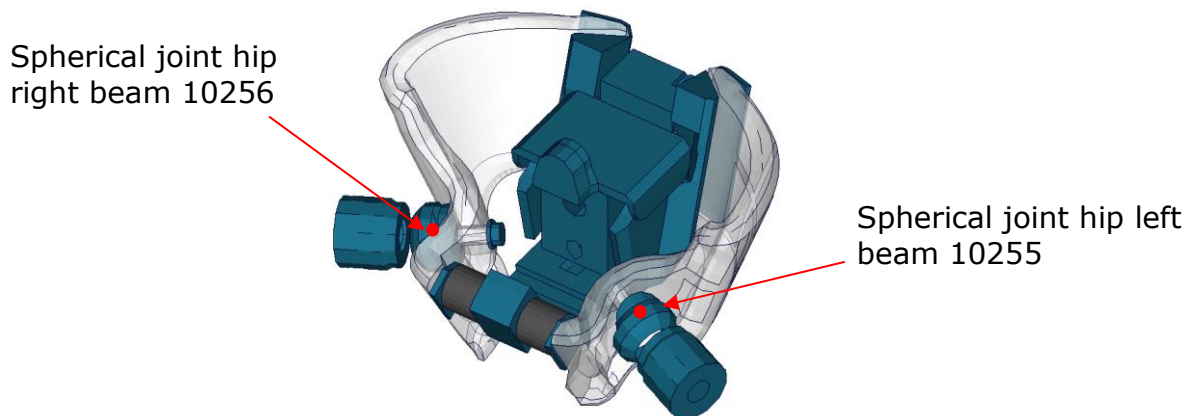


Figure 15: Spherical joint hip global force beams

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)

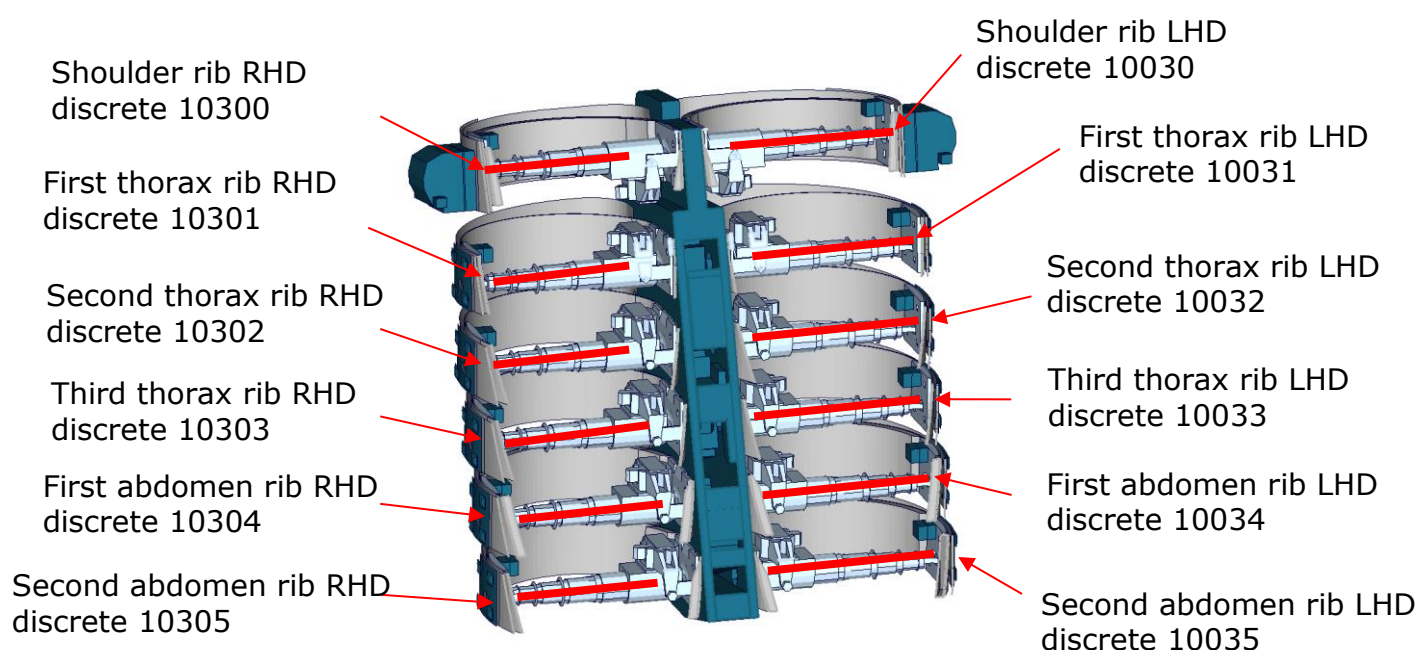


Figure 16: Cut through upper torso and location of rib deflection measurement discretises

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 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)

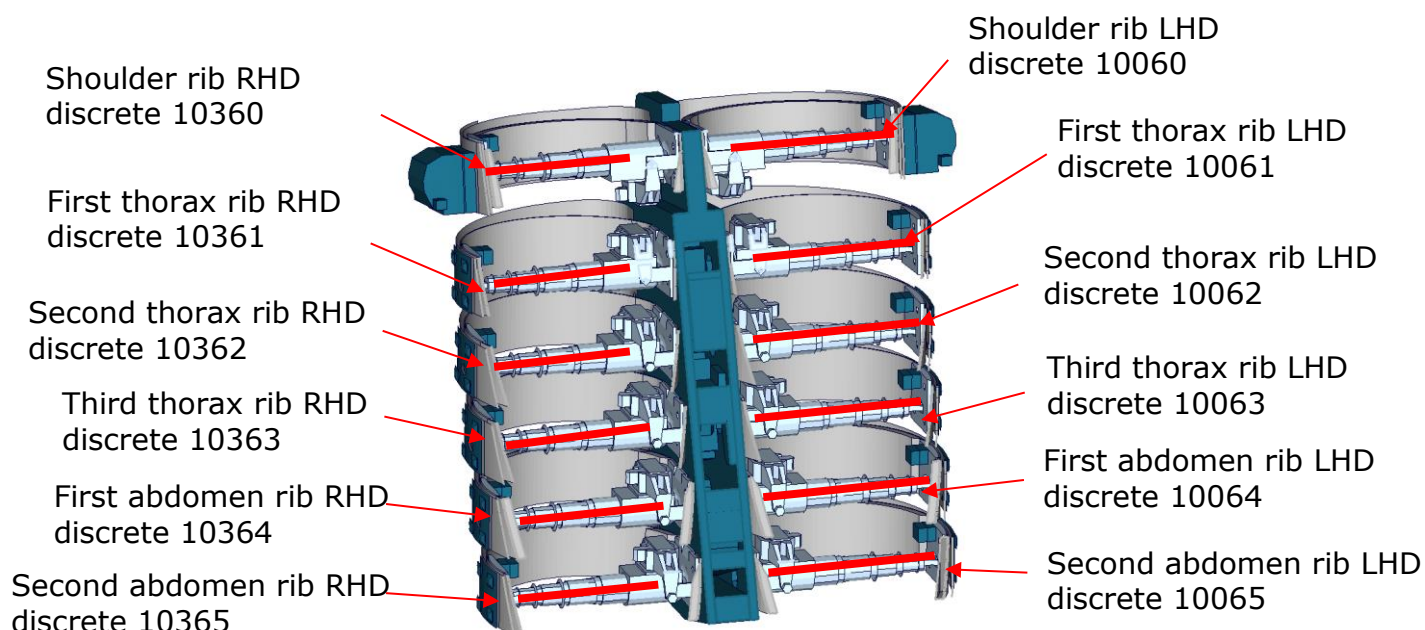


Figure 17: Cut through upper torso and location of rib deflection measurement discretely

Item	Discrete beam-ID	Label	Available components
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)

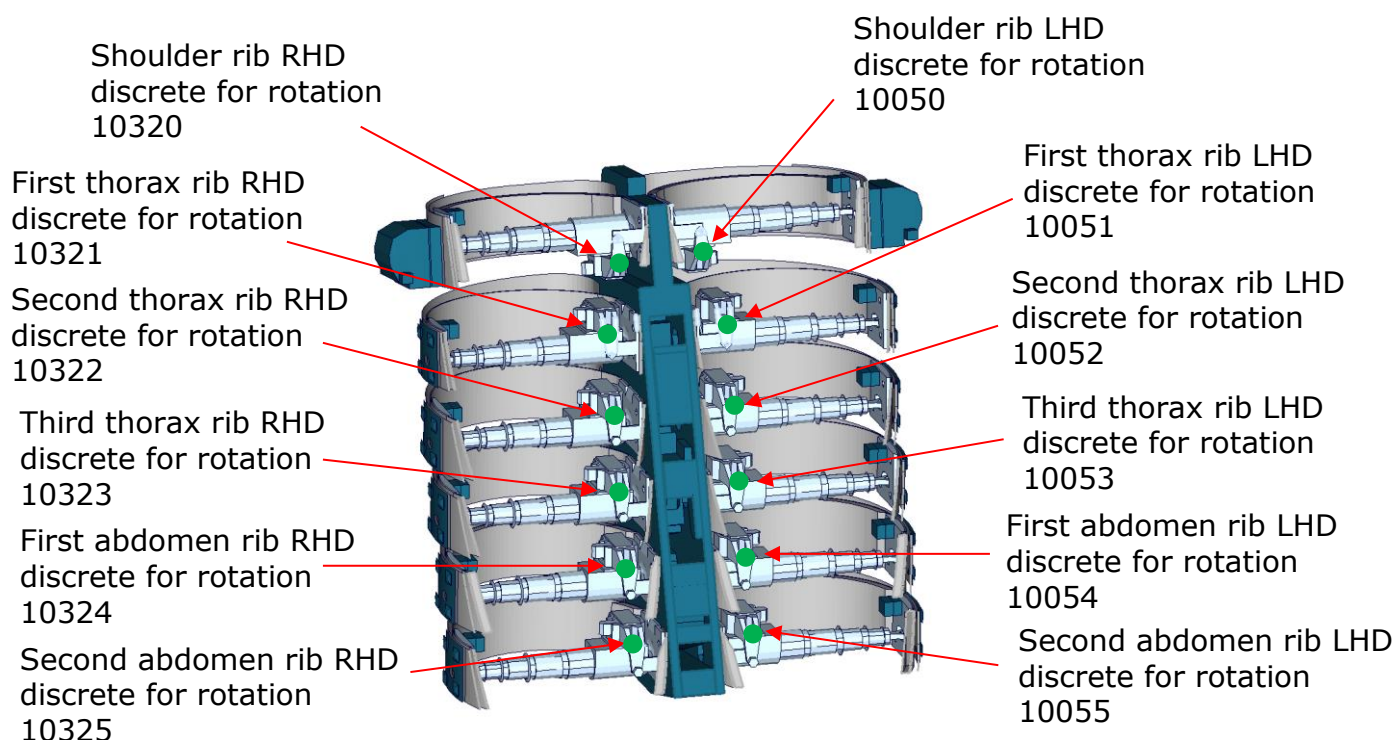


Figure 18: Cut through upper torso and location of rib deflection measurement discretises

Item	Discrete beam-ID	Label	Available components
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	SHRIRI00WSANZ	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

Table 29: Rib Z-rotation measurement using discrete elements (2D IR-TRACCs)

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.

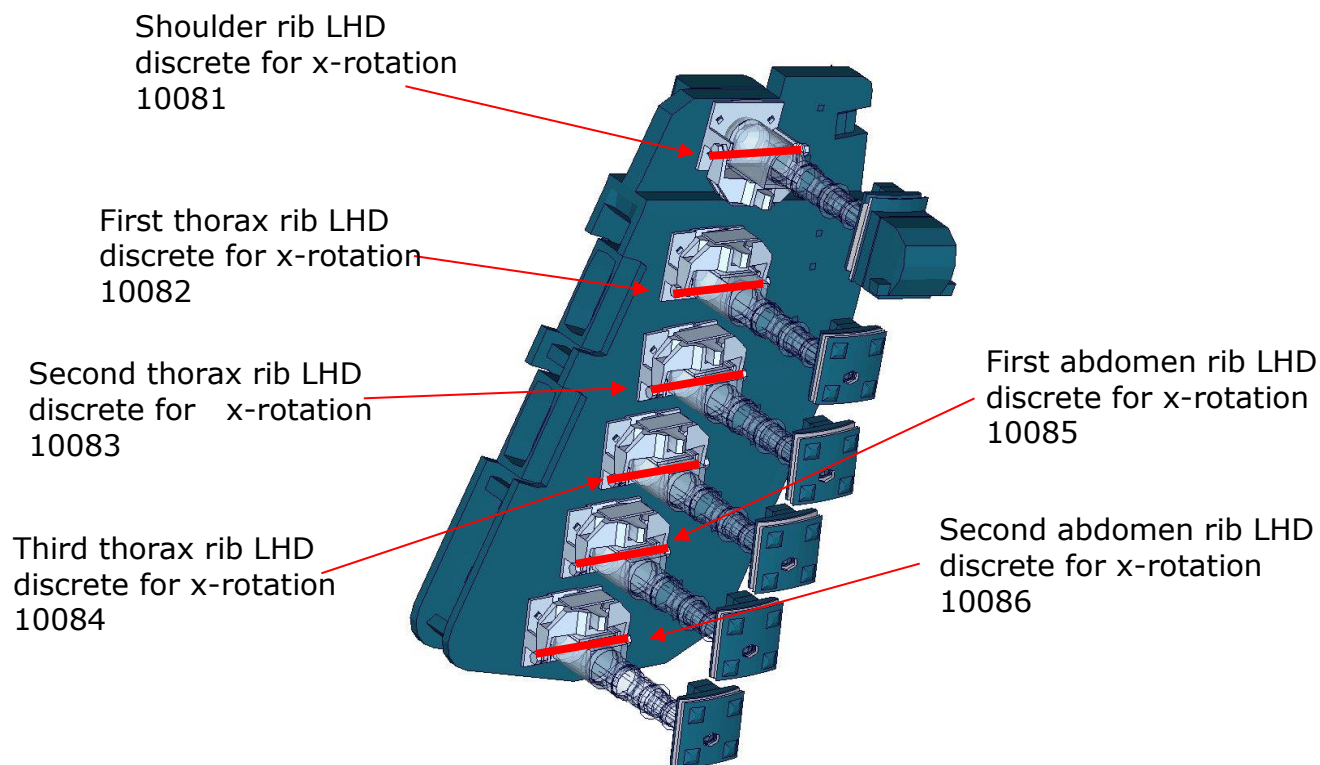


Figure 19: upper torso and location of LHD rib x-rotation measurement discretely

Item	Discrete beam-ID	Label	Available components
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 (3D IR-TRACCs)

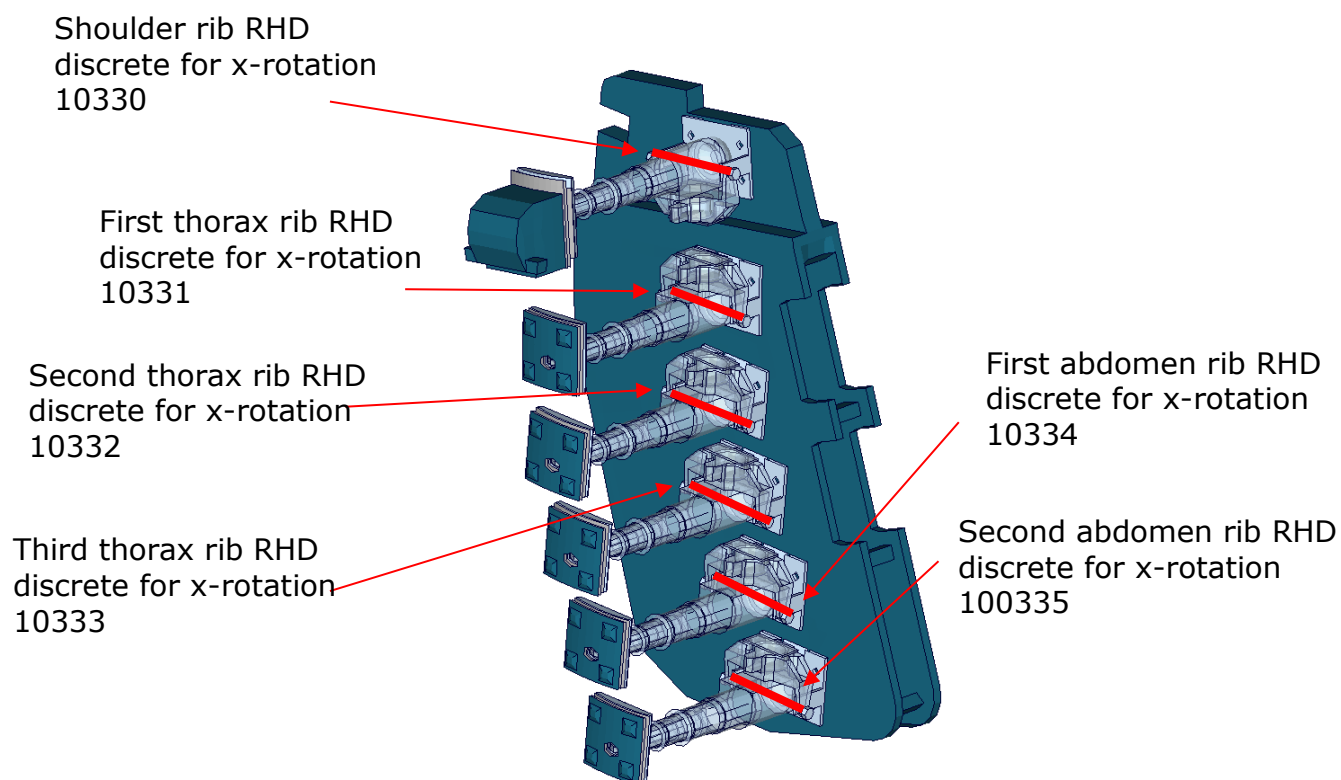


Figure 20: upper torso and location of RHD rib x-rotation measurement discretely

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 (3D IR-TRACCs)

2.4.3 EuroNCAP Lateral Rib Deflection

For EuroNCAP evaluation the local y- deflections in respect to the spine box is calculated by an equation (Euro NCAP TB021):

$$Dy_{rib} = \max(D_y(t) - D_y(0))$$

with:

$$D_y(t) = L(t) \cdot \cos(\alpha(t))$$

L(t) Filtered IR-TRACC length

$\alpha(t)$ Filtered IR-TRACC rotation

$D_y(0)$ Lateral Rib Displacement @ t=0

For Simulation model, a tpl file (Hypergraph evaluation temple file) is applied to output the EuroNCAP evaluation, this will be calculated by:

$$118 - (118 \cdot \cos(\phi_{\text{simulation}}(t)) + (R_{\text{simulation}}(t) \cdot \cos(\phi_{\text{simulation}}(t)))$$

118: the 2D IR_TRACC initial length in model

$R_{\text{simulation}}(t)$ is the output: change in length from

*DATABASE_HISTORY_DISCRETE_ID for IR_TRACC deflection

$\phi_{\text{simulation}}(t)$ is the output: relative rotation(ANZ) from

*DATABASE_HISTORY_DISCRETE_ID for IR_TRACC z rotation

There are .tpl files in delivery data which can evaluate the EuroNCAP Lateral Rib Deflection in page 11 and 12.

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. This method is not applicable any more.

2.4.4 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.

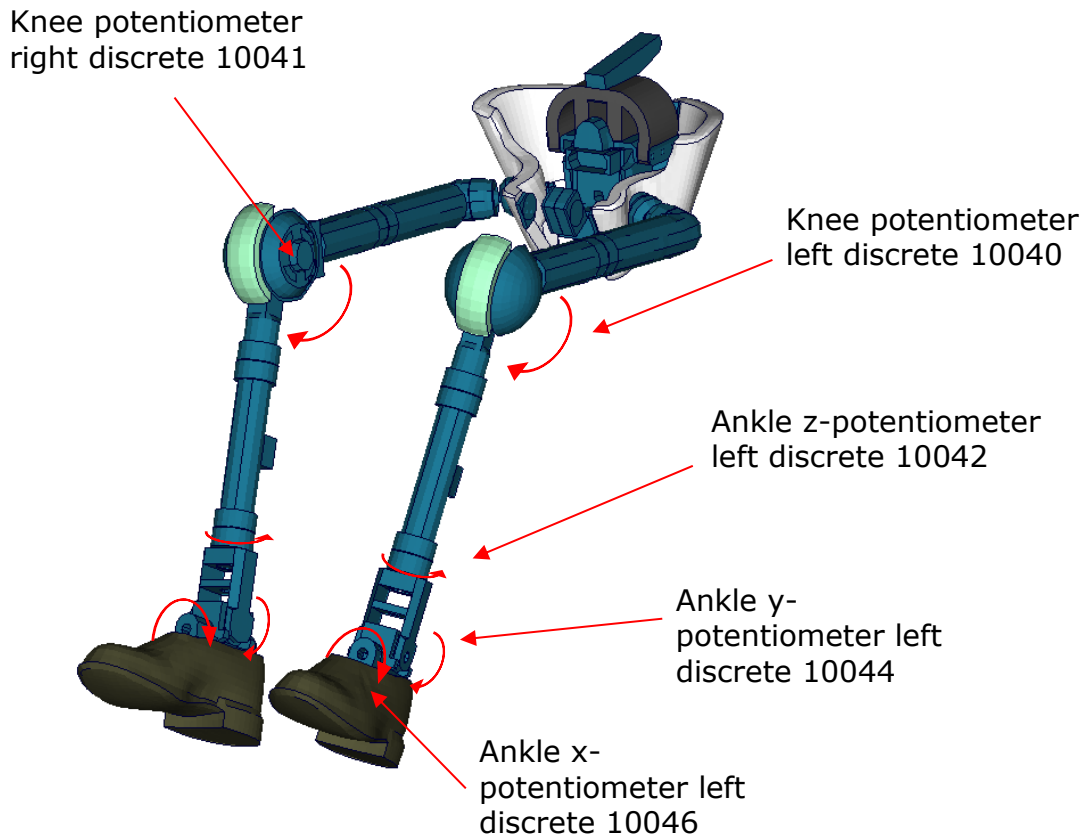


Figure 21: Location of rotation measurement discrete elements in the WorldSID model

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

Table 32: Knee and ankle rotation measurement discrete elements

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:
phi_degree = x-displacement, relative rotation degree of 2D IR-TRACCs
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	SHRILE00WSDS0	y-coordinate	theta_degree
1044	TRRILE01WSDS0	y-coordinate	theta_degree
1045	TRRILE02WSDS0	y-coordinate	theta_degree
1046	TRRILE03WSDS0	y-coordinate	theta_degree
1047	ABRILE01WSDS0	y-coordinate	theta_degree
1048	ABRILE02WSDS0	y-coordinate	theta_degree
1057	SHRIRI00WSDS0	y-coordinate	theta_degree
1058	TRRIRI01WSDS0	y-coordinate	theta_degree
1059	TRRIRI02WSDS0	y-coordinate	theta_degree
1060	TRRIRI03WSDS0	y-coordinate	theta_degree
1061	ABRIRI01WSDS0	y-coordinate	theta_degree
1062	ABRIRI02WSDS0	y-coordinate	theta_degree

Table 33: IR-TRACCs length evaluation

The CONSTRAINED_JOINT_STIFFNESS_GENERALIZED cards IDs are shown as follows:

ID	Title	Local rotation's direction	component
1070	SHRILE00WSANX	x-coordinate	phi_degree
1071	TRRILE01WSANX	x-coordinate	phi_degree
1072	TRRILE02WSANX	x-coordinate	phi_degree
1073	TRRILE03WSANX	x-coordinate	phi_degree
1074	ABRILE01WSANX	x-coordinate	phi_degree
1075	ABRILE02WSANX	x-coordinate	phi_degree
1076	SHRIRI00WSANX	x-coordinate	phi_degree
1077	TRRIRI01WSANX	x-coordinate	phi_degree
1078	TRRIRI02WSANX	x-coordinate	phi_degree
1079	TRRIRI03WSANX	x-coordinate	phi_degree
1080	ABRIRI01WSANX	x-coordinate	phi_degree
1081	ABRIRI02WSANX	x-coordinate	phi_degree
1051	SHRILE00WSANZ	z-coordinate	psi_degree
1052	TRRILE01WSANZ	z-coordinate	psi_degree
1053	TRRILE02WSANZ	z-coordinate	psi_degree
1054	TRRILE03WSANZ	z-coordinate	psi_degree
1055	ABRILE01WSANZ	z-coordinate	psi_degree
1056	ABRILE02WSANZ	z-coordinate	psi_degree
1063	SHRIRI00WSANZ	z-coordinate	psi_degree
1064	TRRIRI01WSANZ	z-coordinate	psi_degree
1065	TRRIRI02WSANZ	z-coordinate	psi_degree
1066	TRRIRI03WSANZ	z-coordinate	psi_degree
1067	ABRIRI01WSANZ	z-coordinate	psi_degree
1068	ABRIRI02WSANZ	z-coordinate	psi_degree

Table 34: IR-TRACCs relative rotation evaluation

2.6 Pelvis Force

In the WorldSID model from version 7.0, it is possible to measure the both 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.

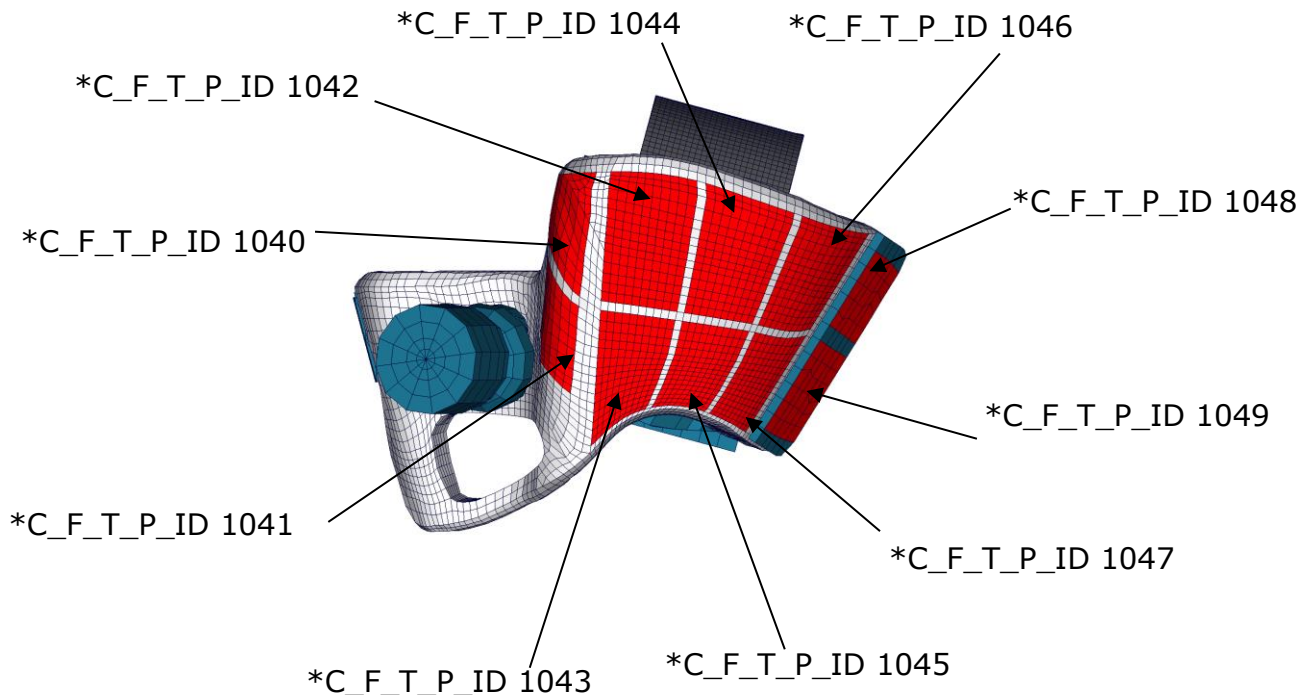


Figure 22: Pelvis left bone is separated into small parts for evaluations

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

Table 35: 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.

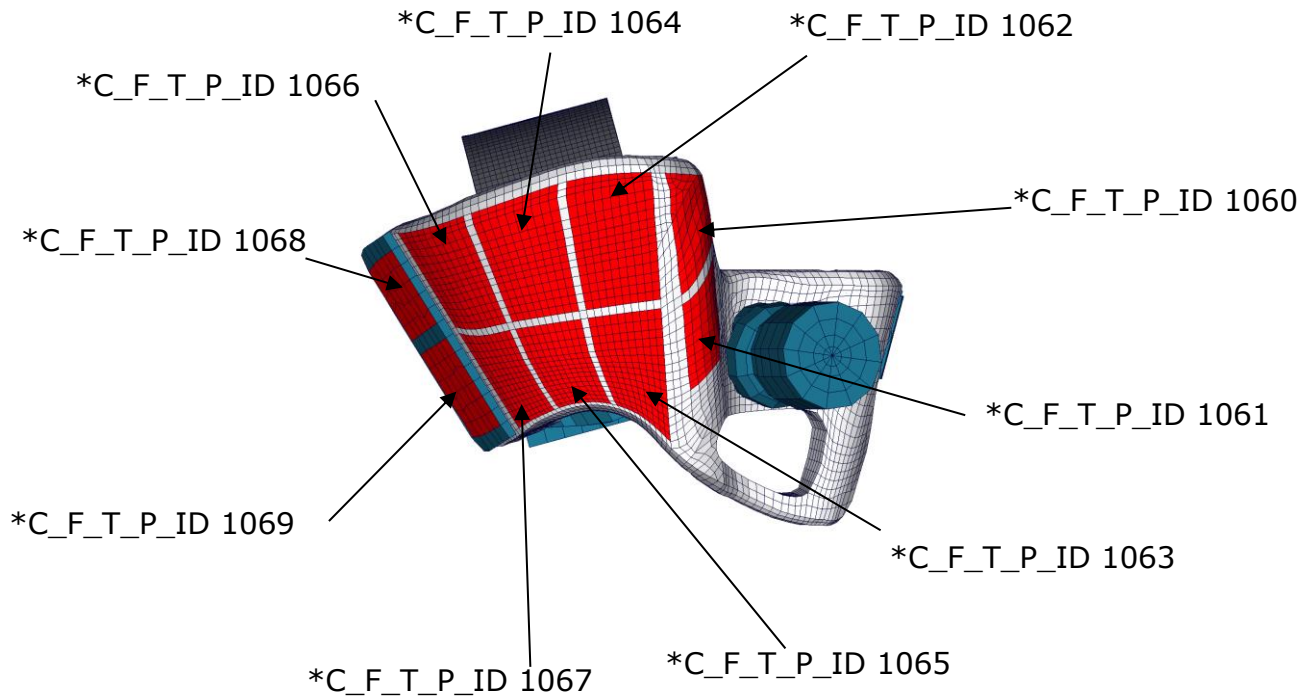


Figure 23: Pelvis right bone is separated into small parts for evaluations

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

Table 36: 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.

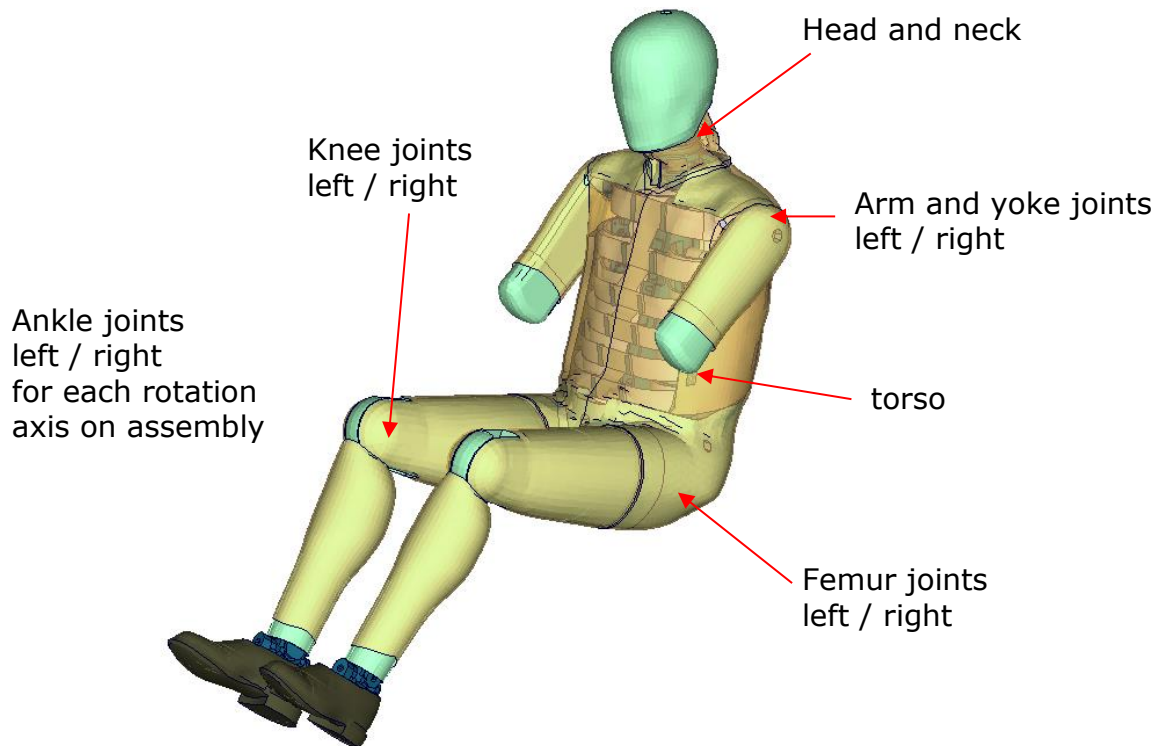


Figure 24: Tree-file assemblies of the WorldSID model.

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.

Movable parts and revolute joints are:

assembly	stop angles
Foot, left and right about their ankle joints local z-axis	stop angle: -21.0 and 21.0 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	stop angle: -140.0 and 100.0 degrees
Yoke	stop angle: -2.0 and 101.0 degrees

Table 37: 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 37. 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.

Since WorldSID v8.0, there is a procedure debug for dummy positioning.

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

The first step is to move the delivery position dummy to the same H-point like your desired position and just replace the nodes in the delivery dummy as the origin position model (Some Preprocessor software can't handle the pre-simulation parameter system). The purpose is to avoid violence pre-simulation with long discrete elements.

The second step is to adapt the posture of the origin position dummy model to your desired position 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.

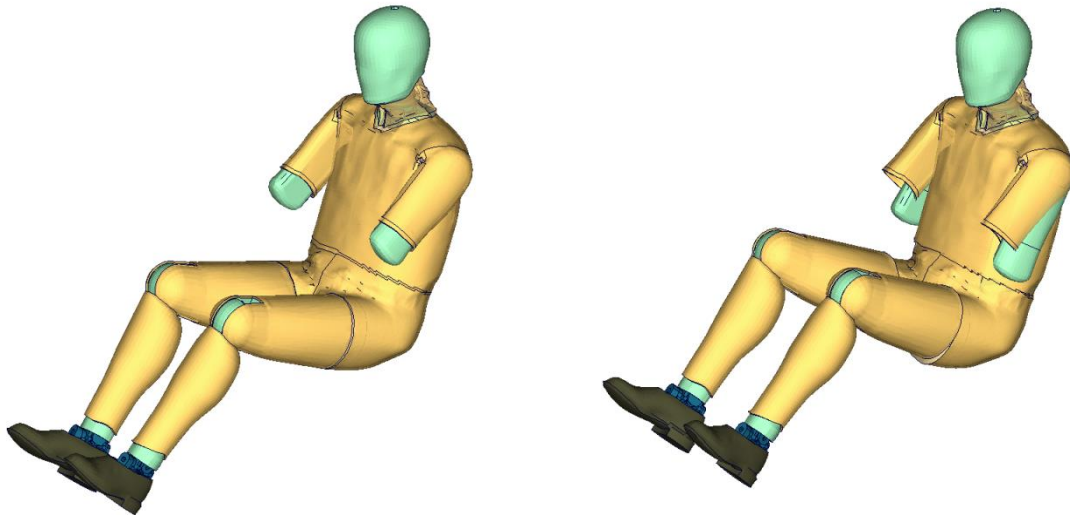


Figure 25: WorldSID origin position (left) and target position (right), besides 2D IR-TRACCs

The third step 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 limbs, there are generated spring and damper elements which pull the limbs in position.

The fourth step is to run the generated input in LS-DYNA and use the results for your actual car.

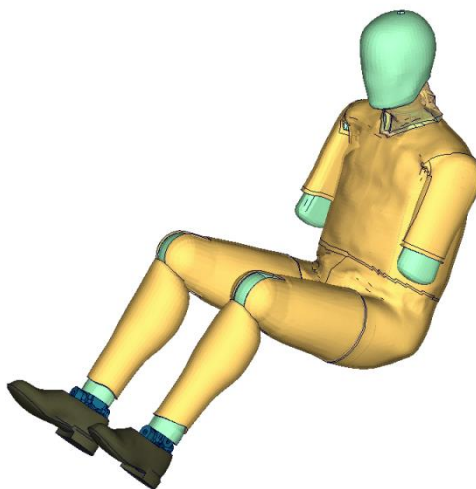


Figure 26: WorldSID position after pre-simulation, besides 2D IR-TRACCs

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

The default termination time in master input which created by psg script is &term =100ms , the defaulter time to move is &tmove = 70ms. If the pre-simulation don't get to the right position in time, the &term and &tmove can be modified to a larger one, e.g &term=150ms, &tmove=120ms, &tmove should be smaller than &term, the recommend gap is about 30ms.

Since WorldSID v7.6, WorldSID IR-TRACCs position can be also executed in the second step.

Here is an example to adapt the posture of the dummy to your desired 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.

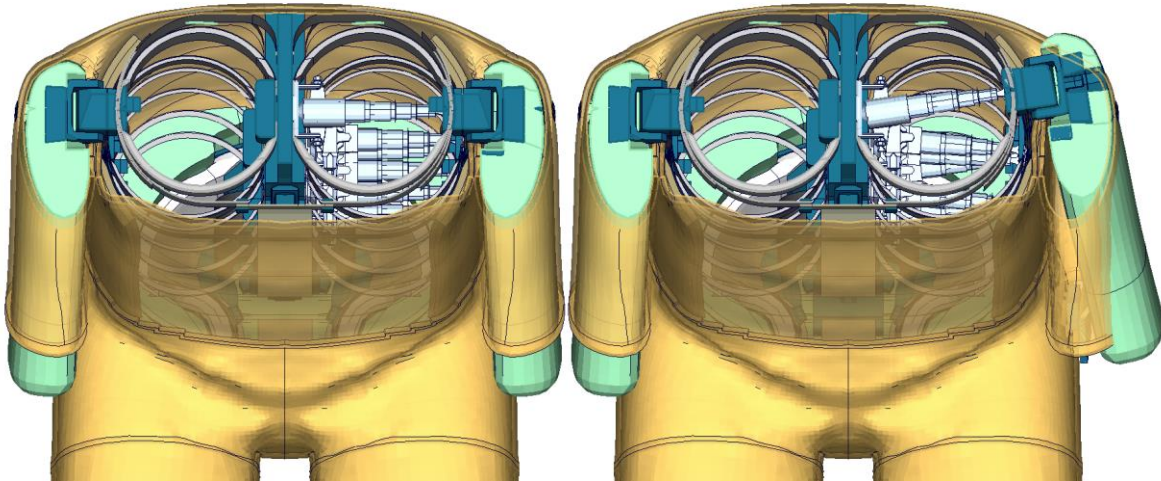


Figure 27: WorldSID IR-TRACCs origin position (left) and target position (right)

Next step is the same as 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
```

Final step is to run the generated input from the previous step in LS-DYNA and use the results for your actual car model as the initial geometry.

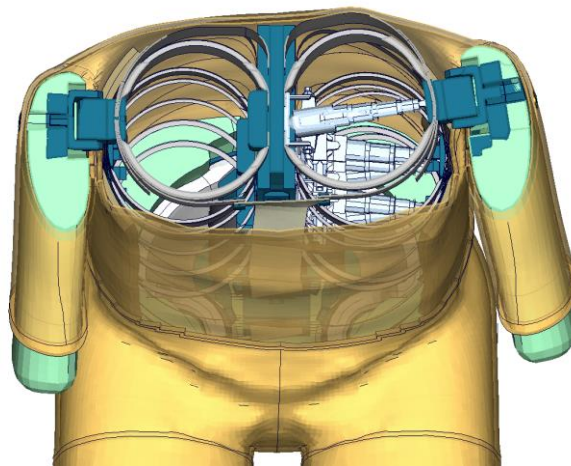


Figure 28: WorldSID position after 2D IR-TRACCs pre-simulation

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.

Pretensions 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.

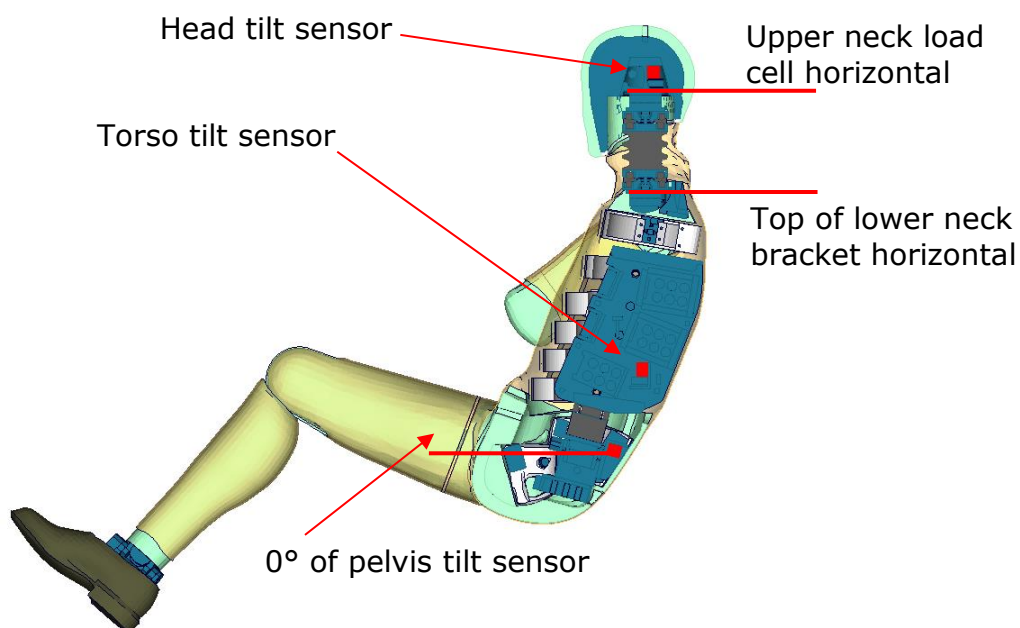


Figure 29: Cut through WorldSID model with positions of tilt sensors

The initial position of the WorldSID model uses a pelvis angle of 0 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.

Additional information about EuroNCAP Position:

From EuroNCAP, torso tilt sensor (pelvis tilt sensor) output is -2 degree for EuroNCAP 23 degree position.

The delivery WorldSID50th model position is from dummy hardware manual, dummy set-up orientations.

For EuroNCAP 23 degree position, the pelvis angle of dummy model should be adjusted from 0 to -2 degree.

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 details please check chapter 1.

The numbering of the material tables and load curves is defined by parameters. If the model should be renumbered all tables and load curves must be renumbered by using the parameter **wsloff**. 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!

- 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. 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 38: 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 wss1002 should be used.

The principle structure is as follows:

Input data in the WorldSID license file:

*PARAMETER

\$ Load Curve offset

I wsloff 0

\$ Load Curve scale values

R wssXXXX 1.0

R wssxXXXX 1.0

*PARAMETER_EXPRESSION_MUTABLE

I wsITABID TABID + &wsloff

R wseTABID 1.0 * & wssXXXX

Input of the license file:

*DEFINE_CURVE

&wsITABID 0 1.0&wseTABID 0.0 0.0

 <Values_x> <Values_y>

 .

 .

 .

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 *PARAMETER 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_v8.0_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_v8.0_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.

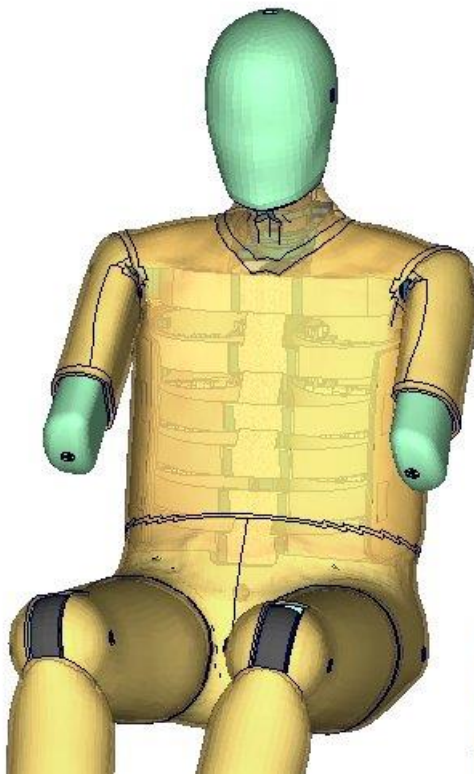
A LS-DYNA simulation in use of the work file will give wrong results and is very unstable. So if you observe dummy model crashes without appreciable load you should check if you included the load-curves-work file instead of the license file.

5. Release Notes

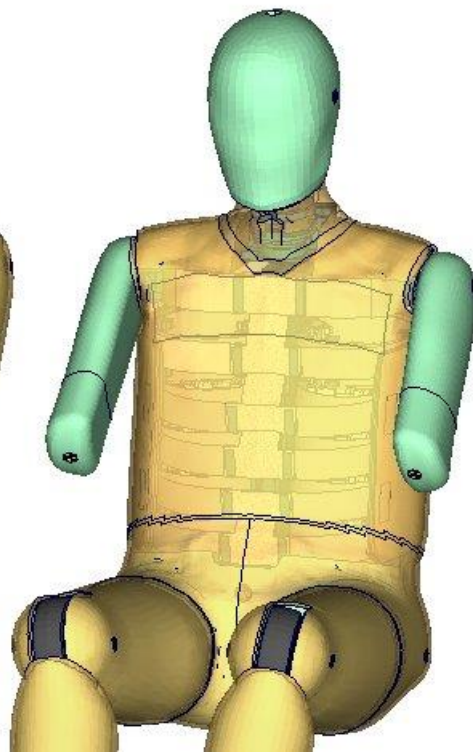
5.1 Release notes of WorldSID v8.0

- Geometric modifications
 - Jacket update to no sleeve model

WSID v7.6.1

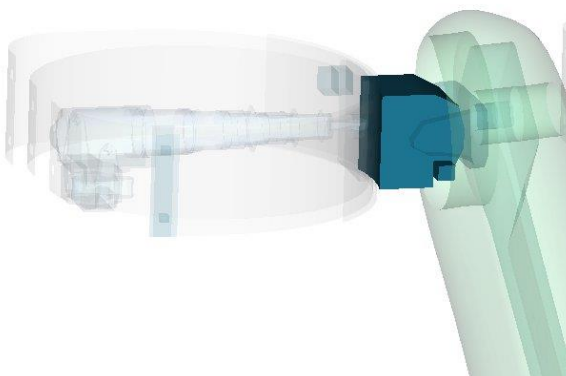


WSID v8.0

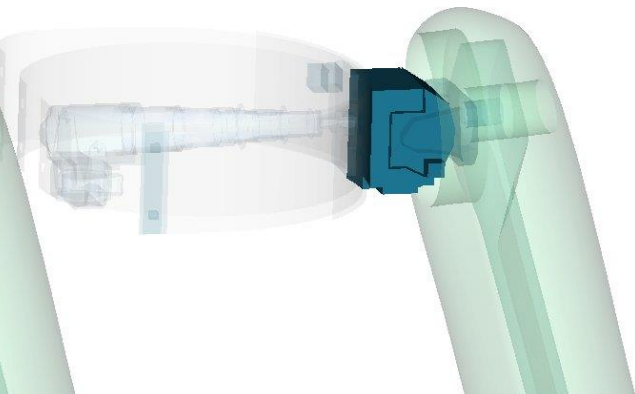


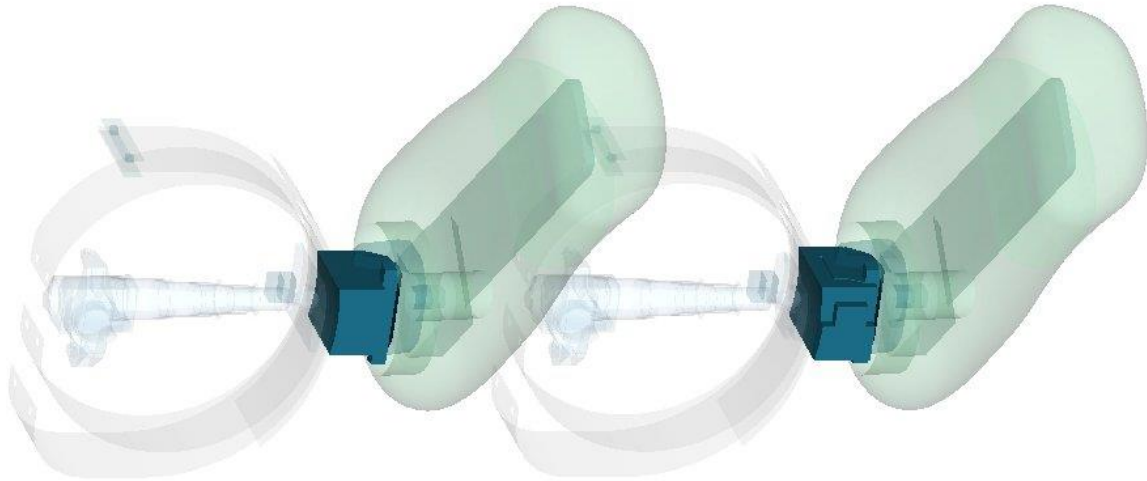
- Shoulder loadcell geometry update

WSID v7.6.1



WSID v8.0

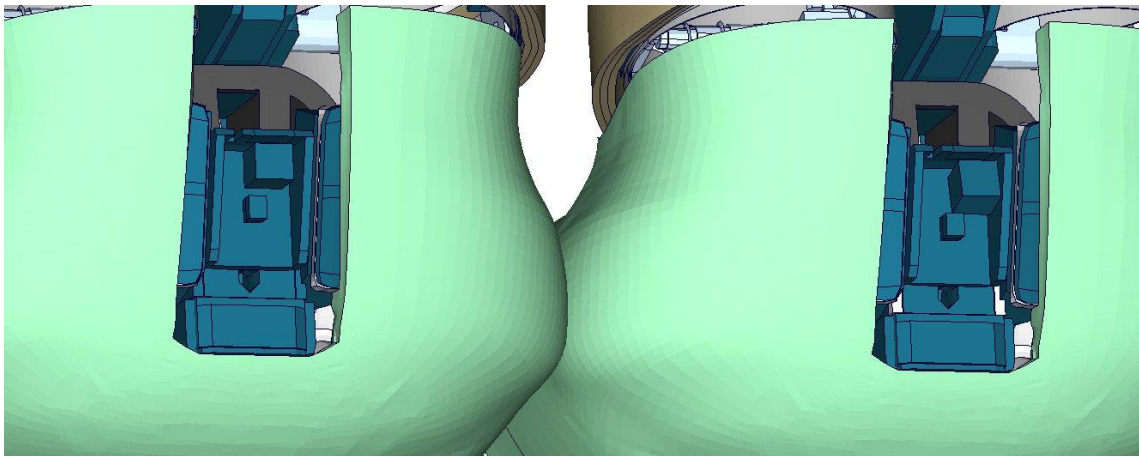




- Pelvis tilt sensor position

WSID v7.6.1

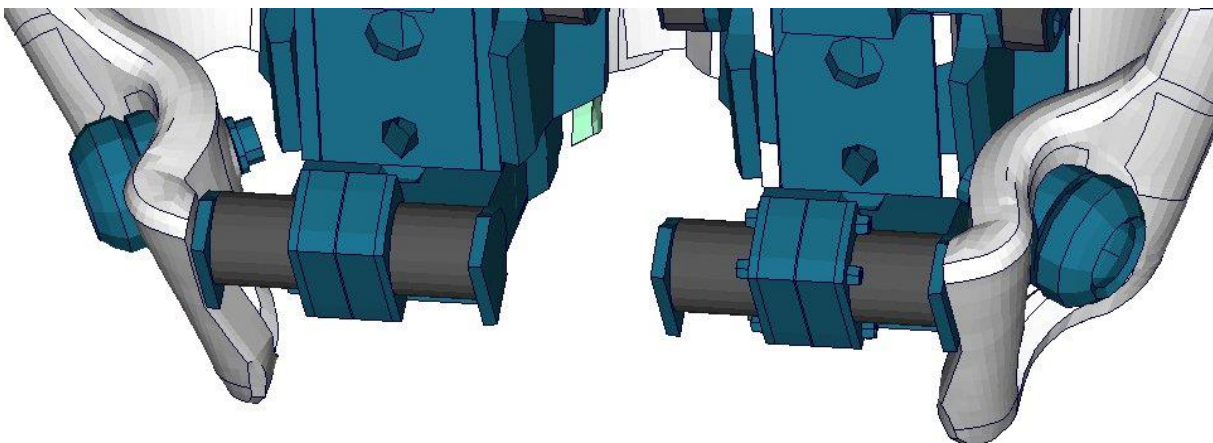
WSID v8.0



- Pubic loadcell with screw geometry

WSID v7.6.1

WSID v8.0



- Euro NCAP far-side virtual testing fulfilling

World SID version 8.0 is the first version with the official certificate of fulfilling all qualification criteria of Technical Bulletin TB 043-1

More details please check the document:

wsid50_pdb_v8.0_manual_VTC_Validation_Report.pdf

- Optional stiffness parameter system for validation performance

The purpose is to get different dummy performance base on dummy validation specifications (corridor).

These parameter are shown in model input on the top of *PARAMETER block:

```
$
*PARAMETER
$
$ Parameters to define the calibration performance.
$ Important information: The delivery parameters combination (&head_opt=1.0,
$ &neck_opt=1.0,&shd_opt=1, &trd_opt=3, &abd_opt=1 and &pel_opt=1.0) is the
$ only one version which is certificated of fulfilling all qualification
$ criteria of Technical Bulletin TB 043-1
$
$ Optional stiffness for head calibration
$ &head_opt == 1.0 : The original delivery stiffness of the head skin
$ &head_opt == 0.61: The Min stiffness of the head skin to catch the drop test
$ &head_opt == 1.31: The Max stiffness of the head skin to catch the drop test
$ &head_opt == 1.0 is the official delivery model
R head_opt 1.0
$
$ Optional stiffness for neck calibration
$ &neck_opt == 1.0 : The original delivery stiffness of the neck rubber
$ &neck_opt == 0.94: The Min stiffness of the neck rubber
$ &neck_opt == 1.12: The Max stiffness of the neck rubber
$ &neck_opt == 1.0 is the official delivery model
R neck_opt 1.0
$
$ Optional thickness for damping-mat of shoulder rib and shoulder calibration
$ &shd_opt == 1: The original delivery thickness of shoulder rib (Damp-MAT)
$ &shd_opt == 2: The Min thickness of shoulder rib (Damp-MAT)
$ &shd_opt == 3: The Max thickness of shoulder rib (Damp-MAT)
$ &shd_opt == 1 is the official delivery model
I shd_opt 1
$
$ Optional thickness for damping-mat of thorax rib and thorax calibration
$ &trd_opt == 1: This optional is just for development purpose(Old BLD)
$ Don't use &trd_opt == 1 for the simulation model since version 8.0
$ &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
$ &trd_opt == 5: The Min thickness of thorax rib (Damp-MAT)
$ &trd_opt == 6: The Max thickness of thorax rib (Damp-MAT)
$ &trd_opt == 3 is the official delivery model
I trd_opt 3
$
$ Optional thickness for damping-mat of abdomen rib and abdomen calibration
$ &abd_opt == 1: The original delivery thickness of abdomen rib (Damp-MAT)
$ &abd_opt == 2: The Min thickness of abdomen rib (Damp-MAT)
$ &abd_opt == 3: The Max thickness of abdomen rib (Damp-MAT)
$ &abd_opt == 1 is the official delivery model
I abd_opt 1
$
$ Optional stiffness for pelvis calibration
$ &pel_opt == 1.0 : The original delivery stiffness of the pelvis foam
$ &pel_opt == 0.94: The Min stiffness of the pelvis foam
$ &pel_opt == 1.36: The Max stiffness of the pelvis foam
$ &pel_opt == 1.0 is the official delivery model
R pel_opt 1.0
$
```

Customer can combine the parameter to get different dummy performance.

Important information: The delivery combination:

&head_opt=1.0

&neck_opt=1.0

&shd_opt=1

&trd_opt=3

&abd_opt=1

&pel_opt=1.0

is the only one version which is certificated of fulfilling all qualification criteria of Technical Bulletin TB 043-1.

The performance please check chapter 8.2.

- In the WorldSID model version 8.0, it is possible to measure the relative x-rotation of IR-TRACCs.

These are measured by key word

CONSTRAINED_JOINTSTIFFNESS_GENERALIZED_TITLE.

The new CONSTRAINED_JOINT_STIFFNESS_GENERALIZED cards IDs are shown as follows:

ID	Title	Local rotation's direction	component
1070	SHRILE00WSANX	x-coordinate	phi_degree
1071	TRRILE01WSANX	x-coordinate	phi_degree
1072	TRRILE02WSANX	x-coordinate	phi_degree
1073	TRRILE03WSANX	x-coordinate	phi_degree
1074	ABRILE01WSANX	x-coordinate	phi_degree
1075	ABRILE02WSANX	x-coordinate	phi_degree
1076	SHRIRI00WSANX	x-coordinate	phi_degree
1077	TRRIRI01WSANX	x-coordinate	phi_degree
1078	TRRIRI02WSANX	x-coordinate	phi_degree
1079	TRRIRI03WSANX	x-coordinate	phi_degree
1080	ABRIRI01WSANX	x-coordinate	phi_degree
1081	ABRIRI02WSANX	x-coordinate	phi_degree

- Mass adjustment, Range of motion adjustment according to ISO_15830_2022
- Loadcell output polarity adjustment basis on SAE J-211
- *MAT optimization for Lumbar, Plevis etc.
- Contact debug for IR-TRACC and Shoulder Loadcell
- IR_TRACCs *CONSTRAINED_JOINT_STIFFNESS_GENERALIZED_TITLE with ISO name
- Element numbering: without overlap between solid and shell element ID
- Ankle joint beams debug
- Right arm joint mechanism debug
- H-point marker position adjustment
- Jacket pre-stress debug for S2 model
- Pre-Simulation optimization

5.2 Release notes of WorldSID v7.6.1

- Update version 7.6.1
 - *MAT_SIMPLIFIED_RUBBER Debug.

5.3 Release notes of WorldSID v7.6

- Update version 7.6
 - Rib coupler contact update.
 - Jacket geometry adjusted for rib coupler contact and thigh angle adjust. Thigh rotated in y direction after +/-3 degrees without pre-simulation, Jacket doesn't have negative volume elements.
 - Lumbar optimized with better component test results.
 - Pelvis flesh,*MAT optimized, *DAMPING_PART_STIFFNESS changed to 0.1
 - *SET_NODE fixed for psg sript(pre-simulation script).

5.4 Release notes of WorldSID v7.5.1

- Update version 7.5.1
 - *DATABASE_HISTORY_NODE_LOCAL_ID update. For EuroNCAP evaluation.
 - IR_TRACC right,
*CONSTRAINED_JOINT_STIFFNESS_TRANSLATIONAL_TITLE debug.
 - Shoulder and pubic load cell updated, from hardware the compression is negative. The polarity of these loadcells is adjusted.
 - Accelerometer *ELEMENT_SEATBELT_ACCELEROMETER update. In order to match the accelerometer hardware better the *ELEMENT_SEATBELT_ACCELEROMETER Parameter IGRAV is changed from 0 to 1.

5.5 Release notes of WorldSID v7.5

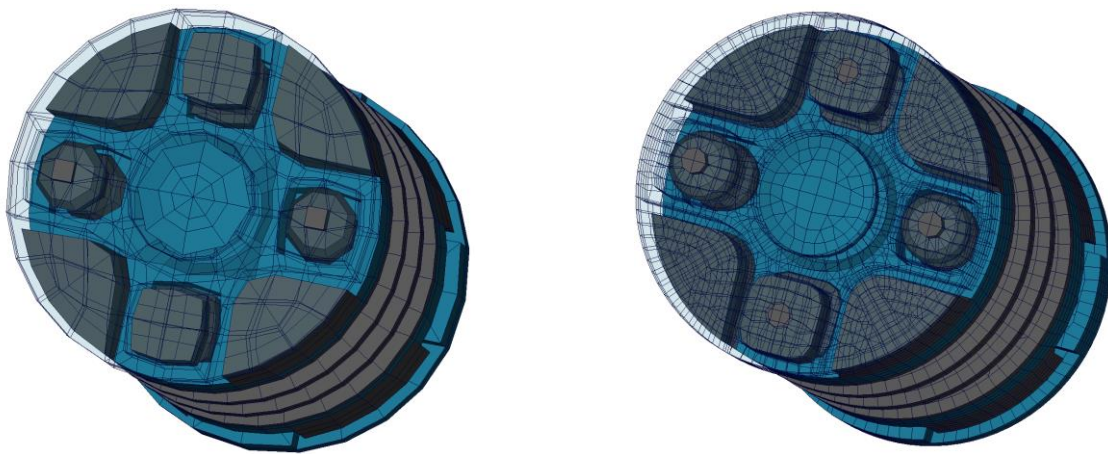
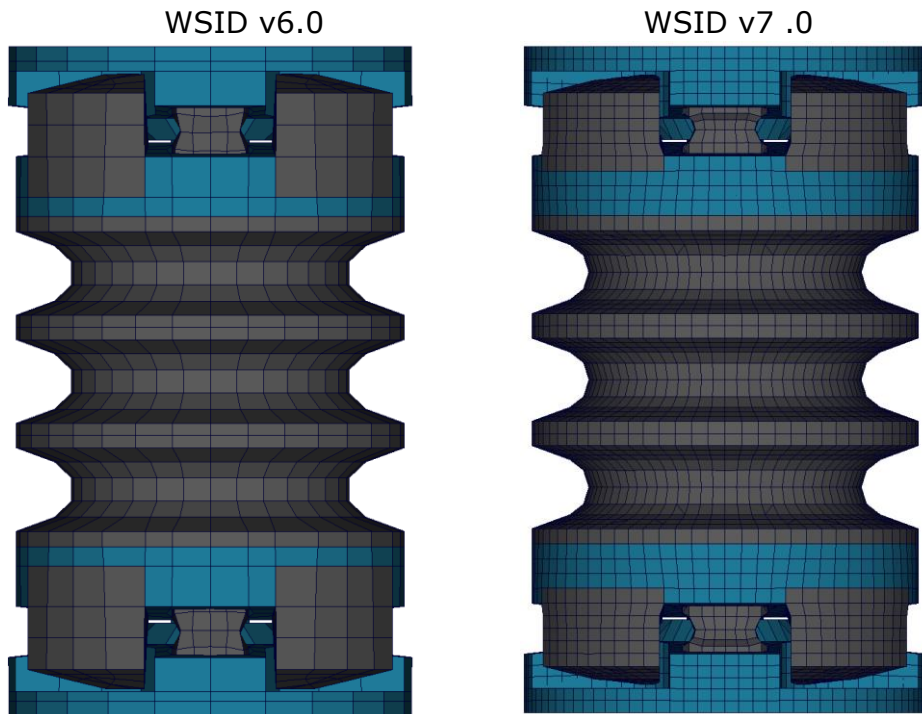
- Update version 7.5
 - Parameters defined by *PARAMETER_EXPRESSION_MUTABLE are now unencrypted.
 - Material and load curve optimizations.
 - IR_TRACCs, Pelvis etc. with contact update.
 - Rib mounting bracket with geometric update.

5.6 Release notes of WorldSID v7.1

- Update version 7.1
 - Several material curve optimizations.
 - Pelvis contact and material fixed.
 - Friction parameters of right side thorax are adjusted.
 - The update's purpose is to improve the stability of the model, there is no influence on the simulation curves of the model.

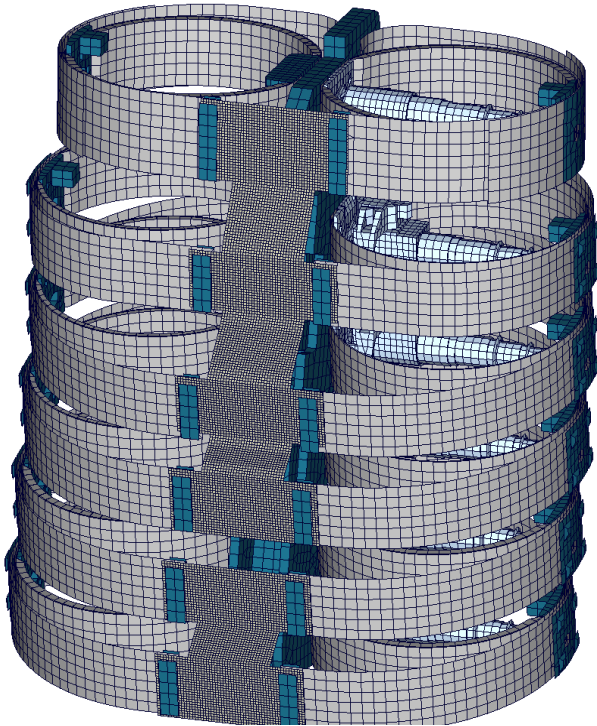
5.7 Release notes of WorldSID v7.0

- Geometric modifications
 - Finer neck, from 3mm~9mm to 2.5mm

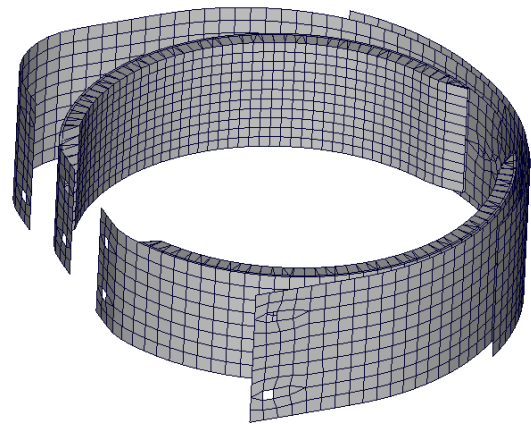
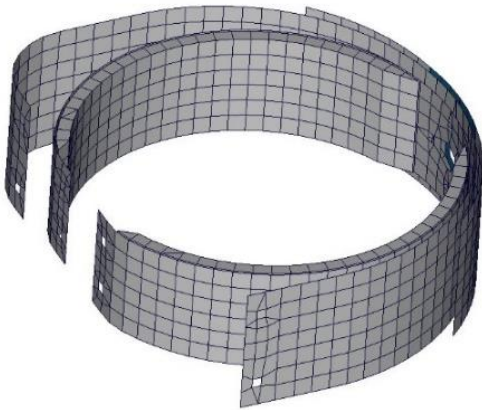
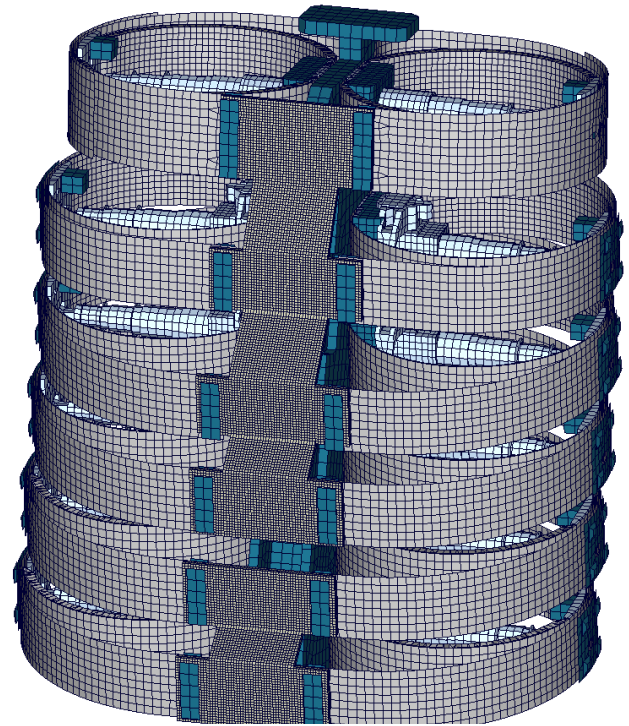


- Finer thorax

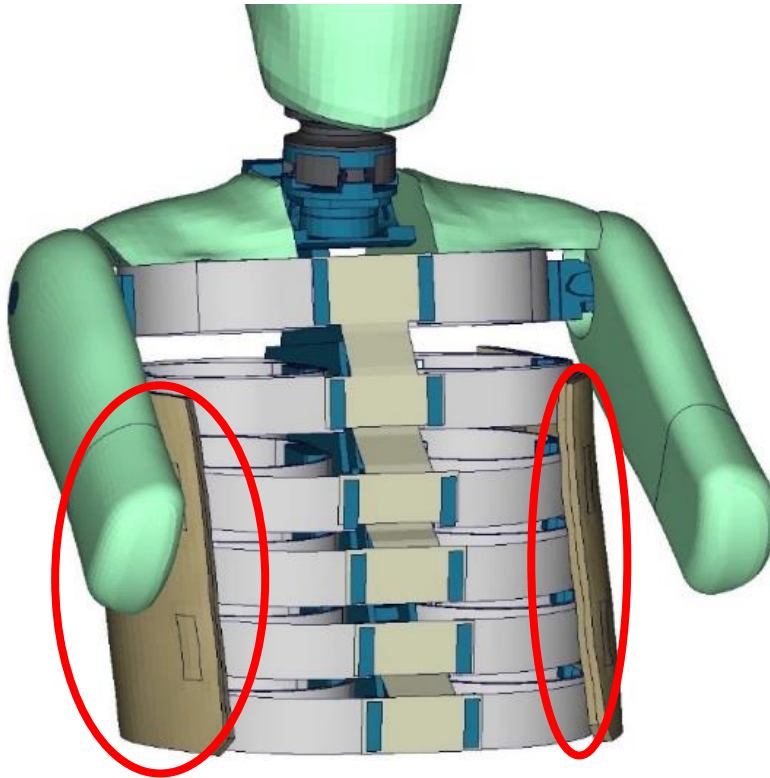
WSID v6.0



WSID v7 .0

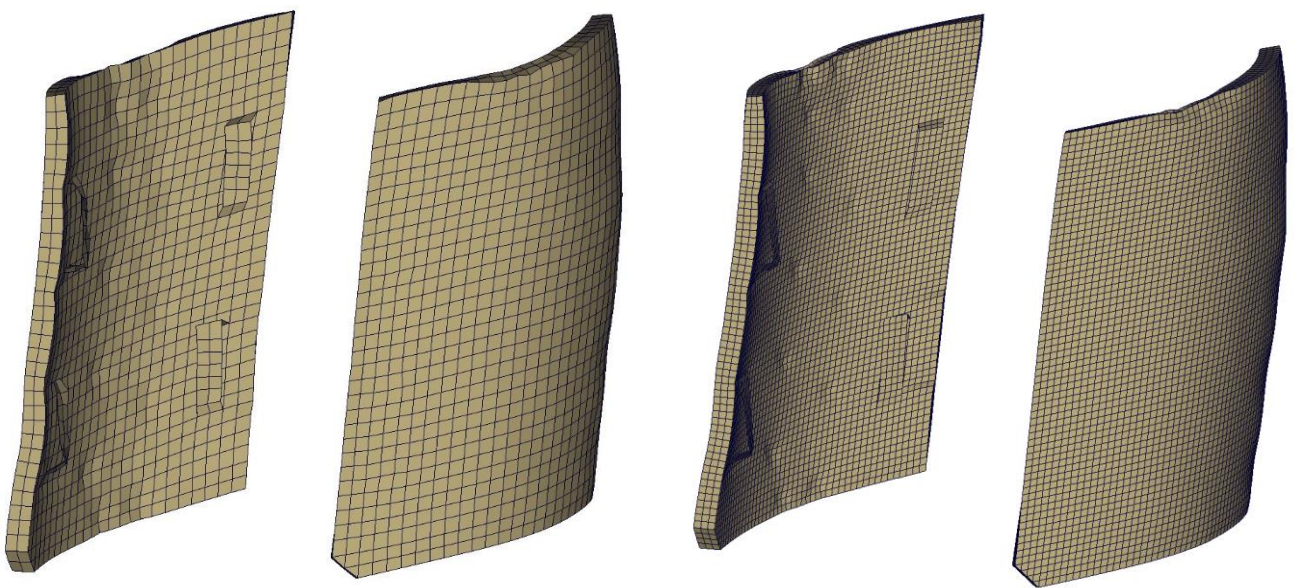


- Finer thorax-Pad, from 8mm to 4mm, in order to compare to finer thorax rib and jacket

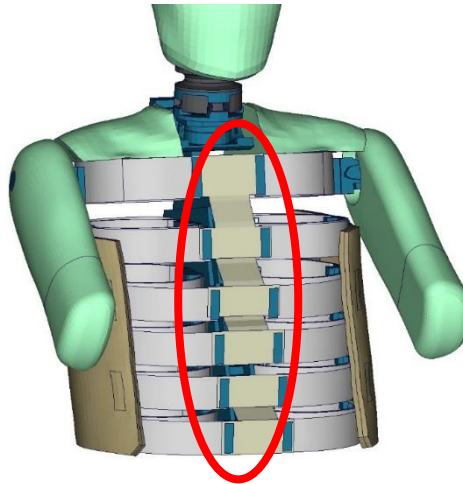


WSID v6.0

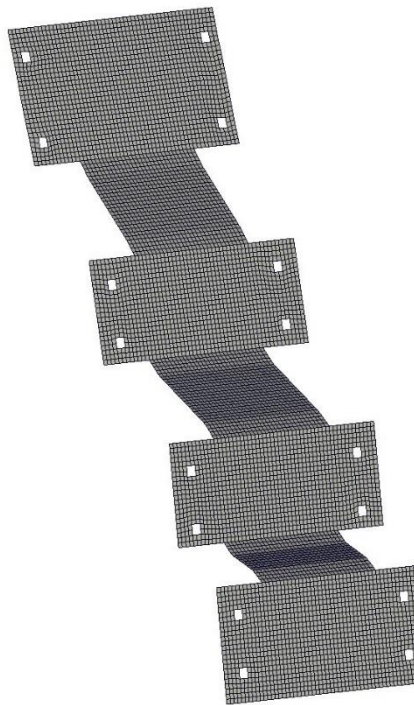
WSID v7 .0



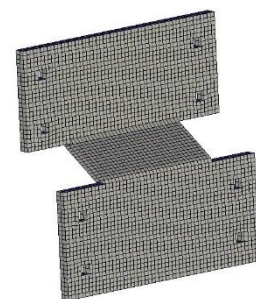
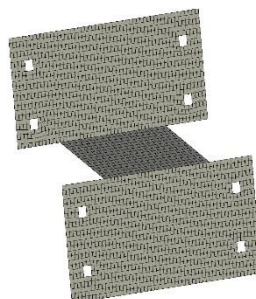
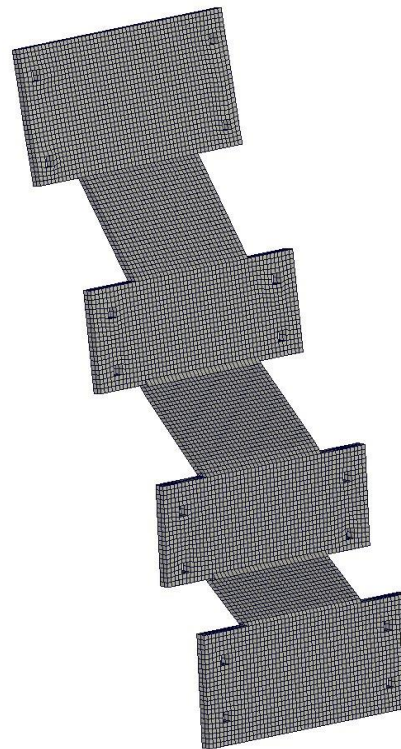
- Solid rib couple: Rib couple is modified from shell elements to two layers solid elements with MAT 181 simplified rubber



WSID v6.0

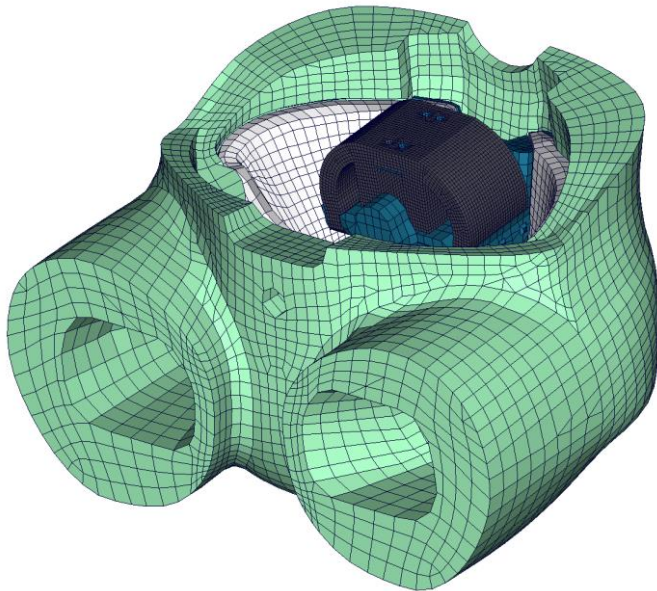


WSID v7.0

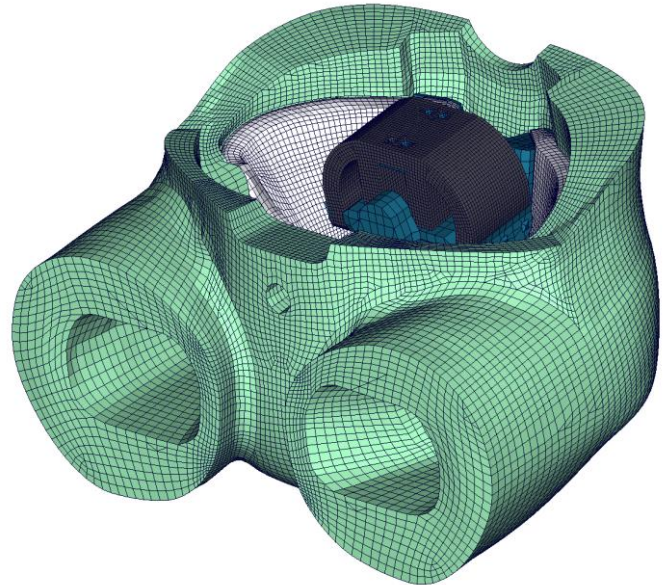


- Finer pelvis and iliac wing

WSID v6.0



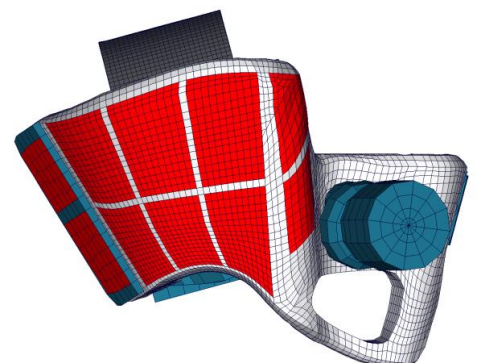
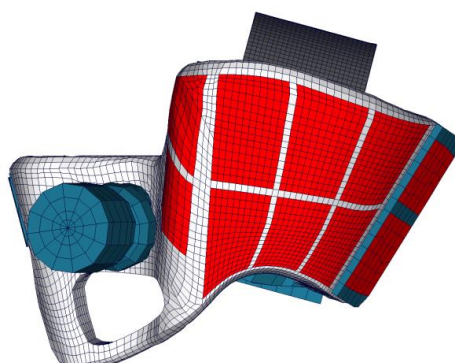
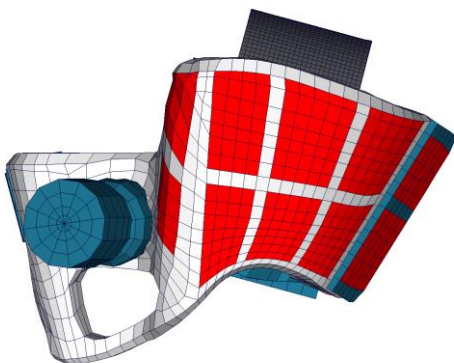
WSID v7.0



WSID v6.0 iliac wing left

v7.0 iliac wing left

v7.0 iliac wing right



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:

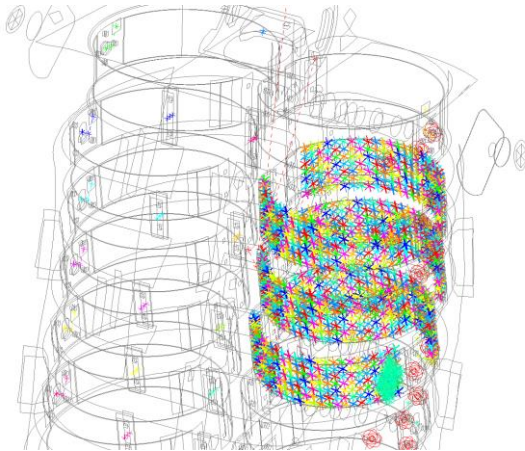
The optional nodes are constrained by:

*CONSTRAINED_NODAL_RIGID_BODY

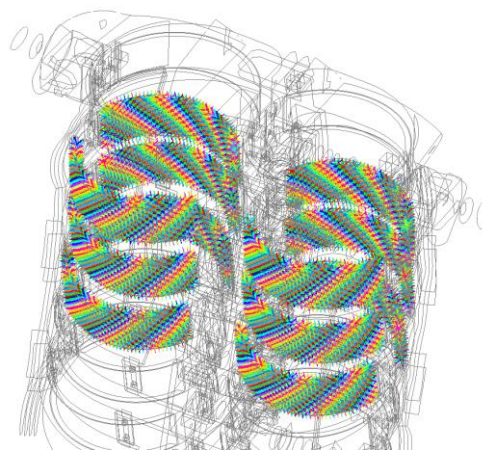
This feature is available for both side of thorax-rib's damping material from version 7.0.

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.

WSID v6.0



WSID v7.0



- 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 Arm sleeve H-point tool RibEye / RibEye_RHD	License(asc file) / Load curves file Arm sleeve H-point tool 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:

- 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
- 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
- worldSID50_pdb_vx.x.x_Ballast_left_vx.x.key**
- worldSID50_pdb_vx.x.x_Ballast_right_vx.x.key**
- 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
- 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	SHRIRI00WSANZ	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	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
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 from the nodout file for LHD and RHD. Nodes are defined:

Item	Node-ID	Label	Available components
shoulder rib LHD	10751	shoulder left rib deformation Local X/Y/Z	x-, y-, z-displacement
1. thorax rib LHD	10752	1 thorax left rib deformation Local X/Y/Z	x-, y-, z-displacement
2. thorax rib LHD	10753	2 thorax left rib deformation Local X/Y/Z	x-, y-, z-displacement
3. thorax rib LHD	10754	3 thorax left rib deformation Local X/Y/Z	x-, y-, z-displacement
1. abdomen rib LHD	10755	1 abdomen left rib deformation Local X/Y/Z	x-, y-, z-displacement
2. abdomen rib LHD	10756	2 abdomen left rib deformation Local X/Y/Z	x-, y-, z-displacement
shoulder rib RHD	10781	shoulder right rib deformation Local X/Y/Z	x-, y-, z-displacement
1. thorax rib RHD	10782	1 thorax right rib deformation Local X/Y/Z	x-, y-, z-displacement
2. thorax rib RHD	10783	2 thorax right rib deformation Local X/Y/Z	x-, y-, z-displacement
3. thorax rib RHD	10784	3 thorax right rib deformation Local X/Y/Z	x-, y-, z-displacement
1. abdomen rib RHD	10785	1 abdomen right rib deformation Local X/Y/Z	x-, y-, z-displacement
2. abdomen rib RHD	10786	2 abdomen right rib deformation Local X/Y/Z	x-, y-, z-displacement

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:

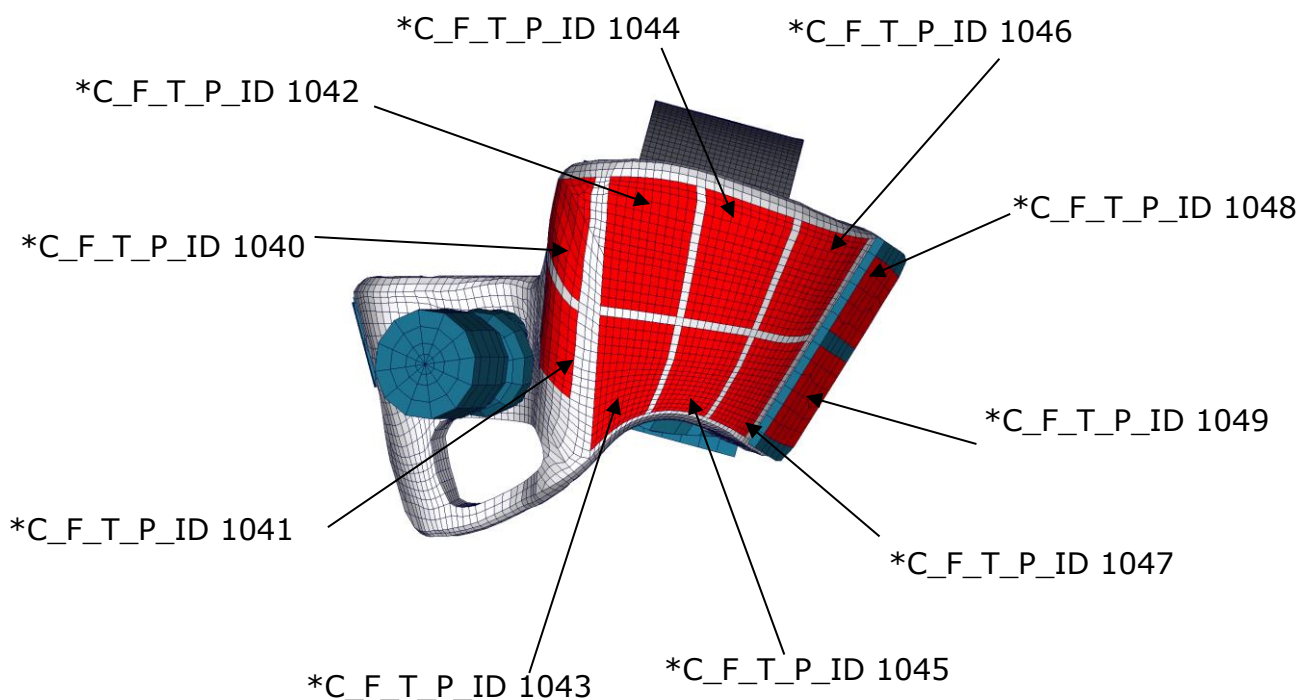
ID	Title	Local direction	component
1043	IR Tracc Shoulder rib length left	y-coordinate	theta_degree
1044	IR Tracc 1st Thorax rib length left	y-coordinate	theta_degree
1045	IR Tracc 2nd Thorax rib length left	y-coordinate	theta_degree
1046	IR Tracc 3rd Thorax rib length left	y-coordinate	theta_degree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

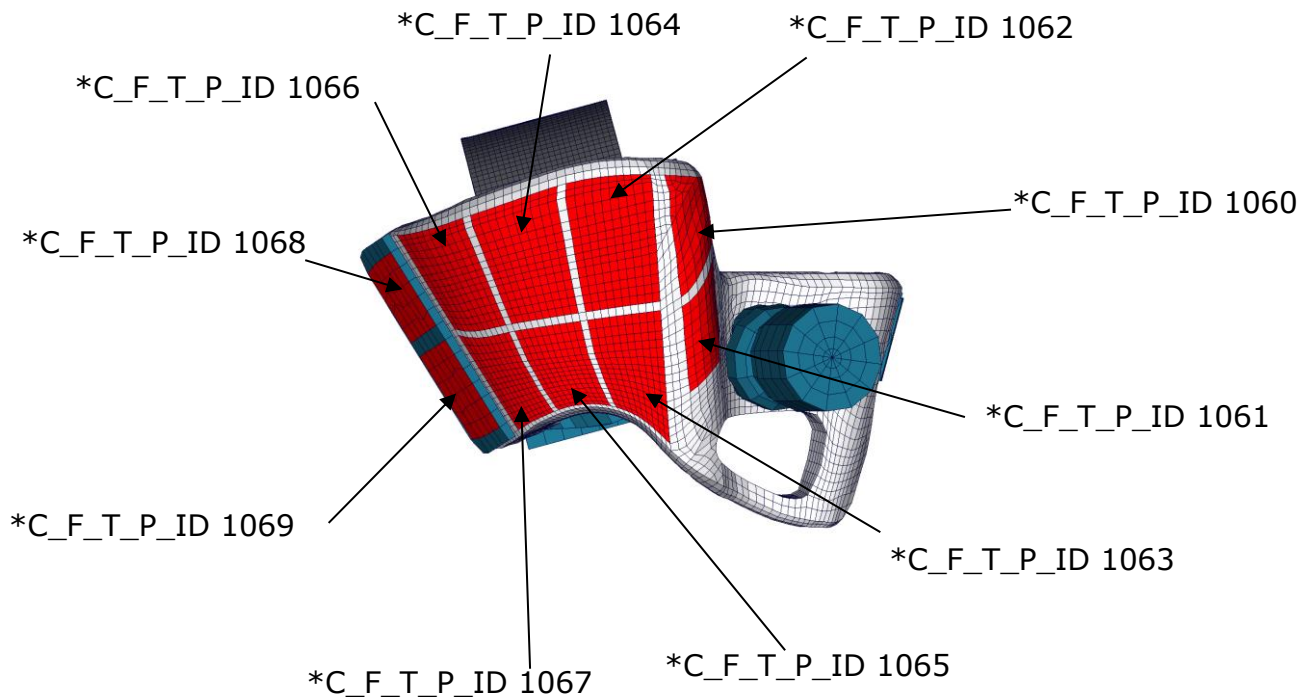
- In the WorldSID model from version 7.0, the measurement of the pelvis force are available for both sides (LHD and RHD). Pelvis bone is separated into small parts for evaluations through *CONTACT_FORCE_TRANSducer_PENALTY_ID.

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

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



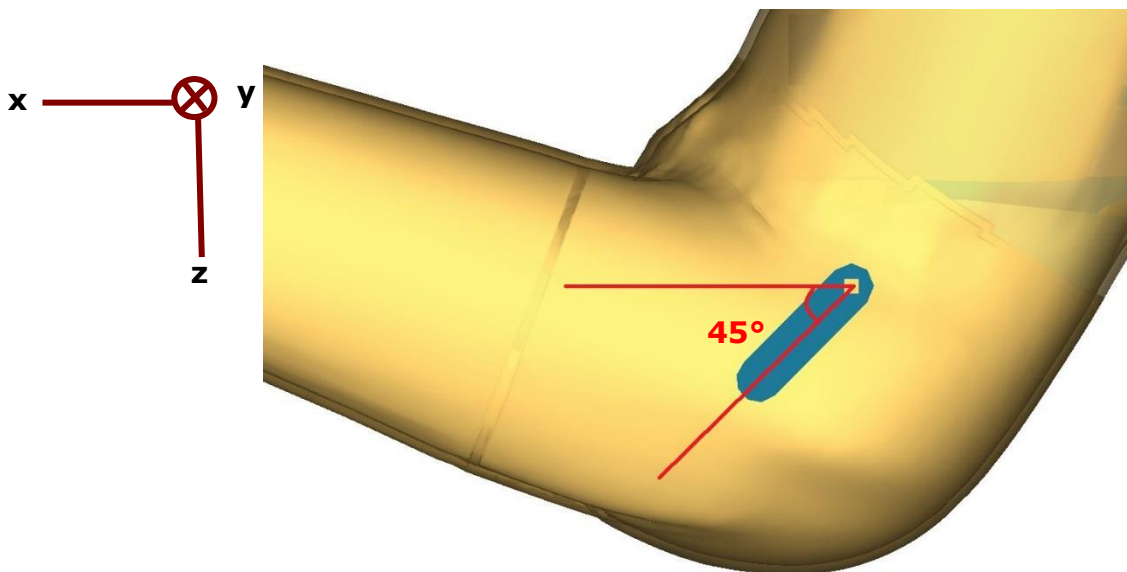
Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1060	pelvis bone force right - upper front	global contact force x-,y-,z-, resultant ;
Pelvis Force	1061	pelvis bone force right - lower front	global contact force x-,y-,z-, resultant ;
Pelvis Force	1062	pelvis bone force right - upper side forward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

5.8 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

1: Global Coordinate Sys	0.0	0.0	0.0
2: Pelvis	0.0	15.0	0.0
3: Torso	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
10: Femur right	0.0	0.0	0.0

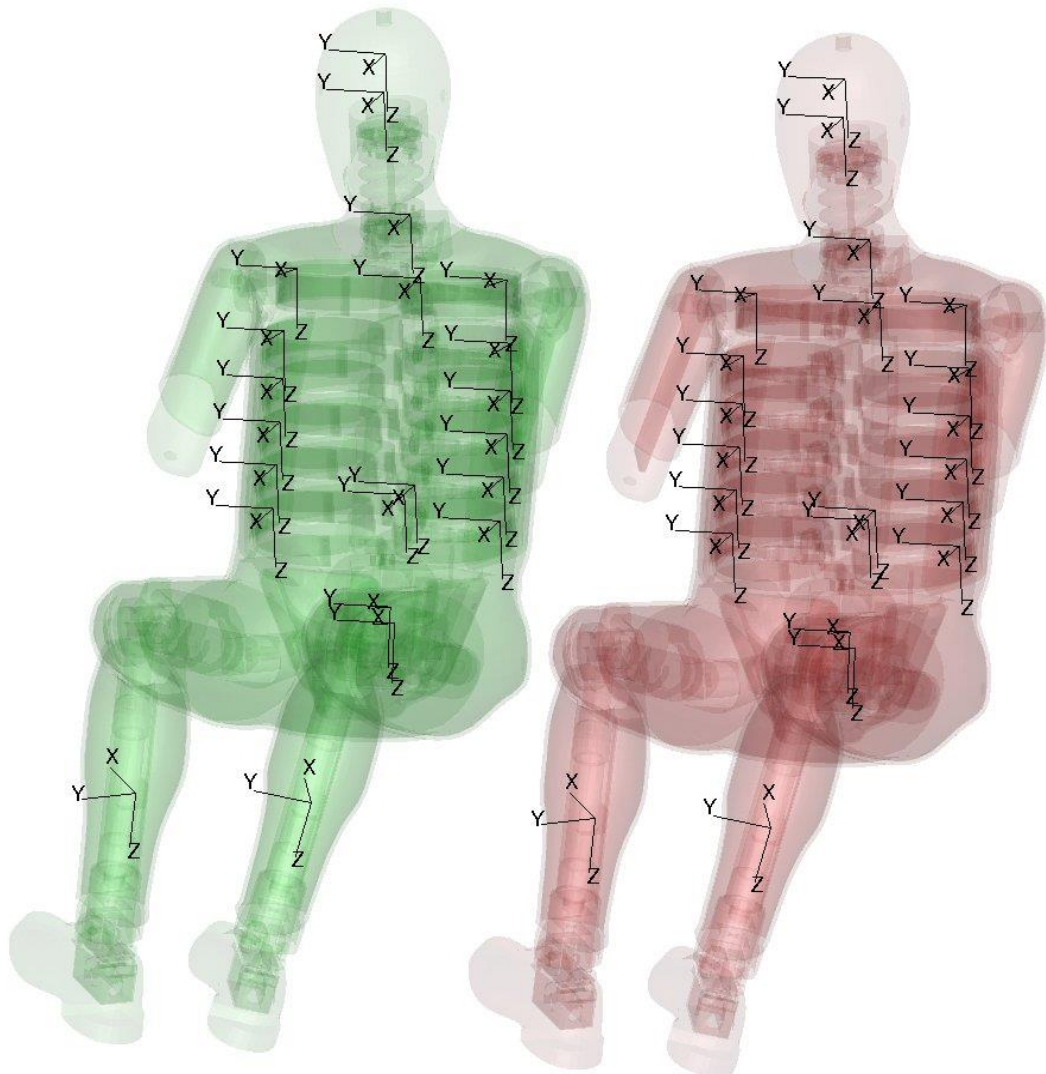
WSID50th V6.0.1

1: Global Coordinate Sys	0.0	0.0	0.0
2: Pelvis	0.0	0.0	0.0
3: Torso	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
10: Femur right	0.0	0.0	0.0

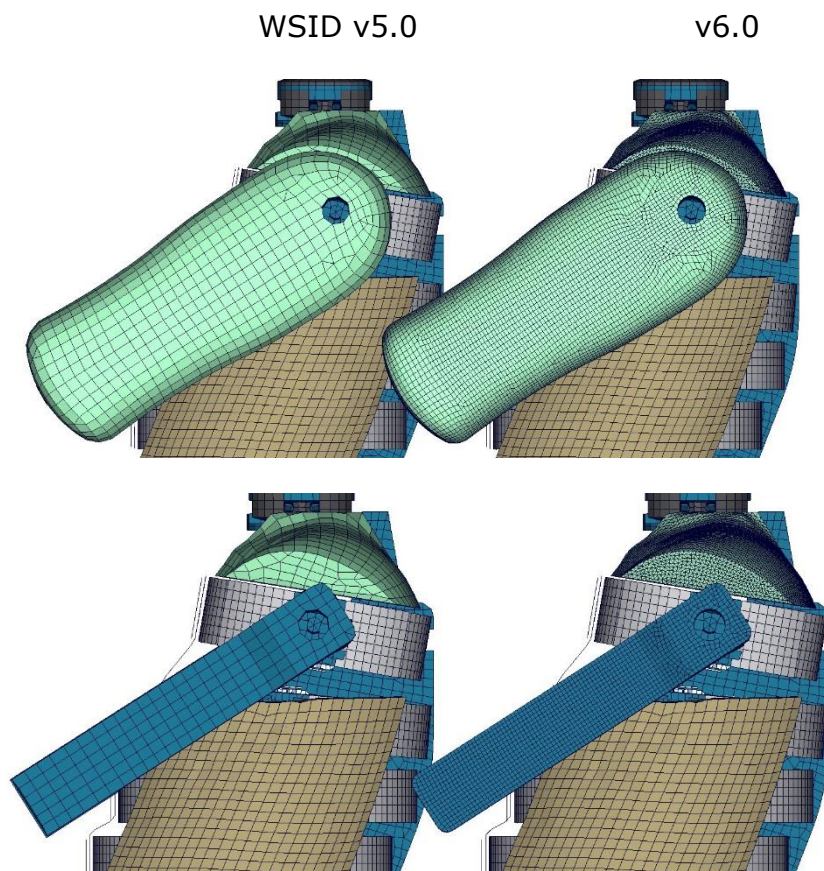
- The Right_Hand_Dummy model has the same coordinate system as the Left_Hand_Dummy model for output. Both base on SAE J211.

WSID50th V6.0 LHD

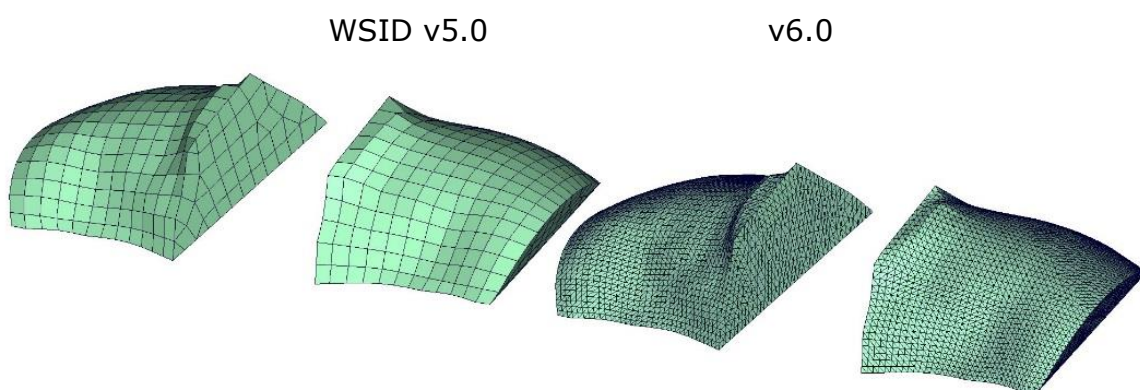
WSID50th V6.0 RHD



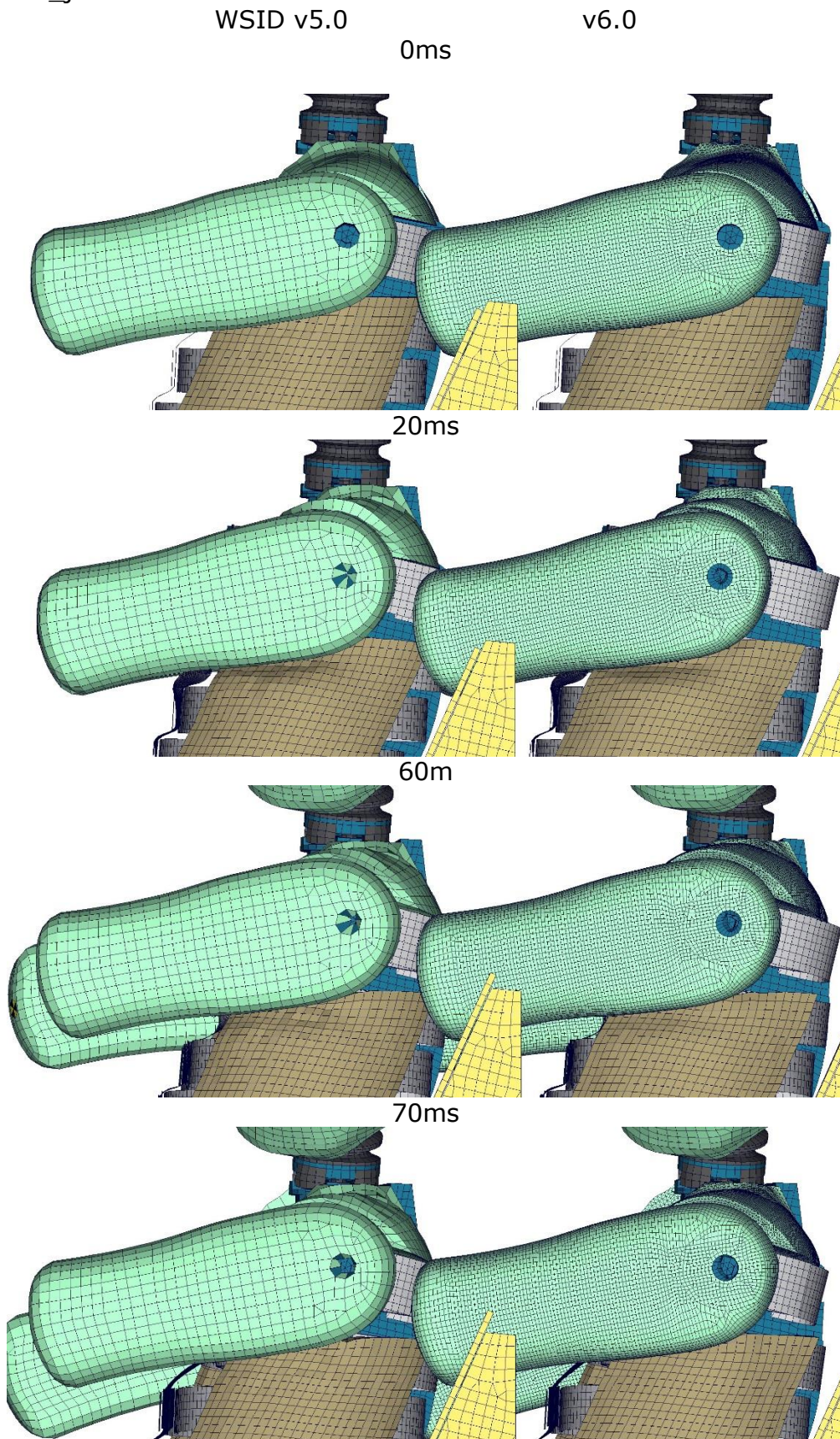
- Geometric modifications
 - Half arm is with new mesh and some material are updated.



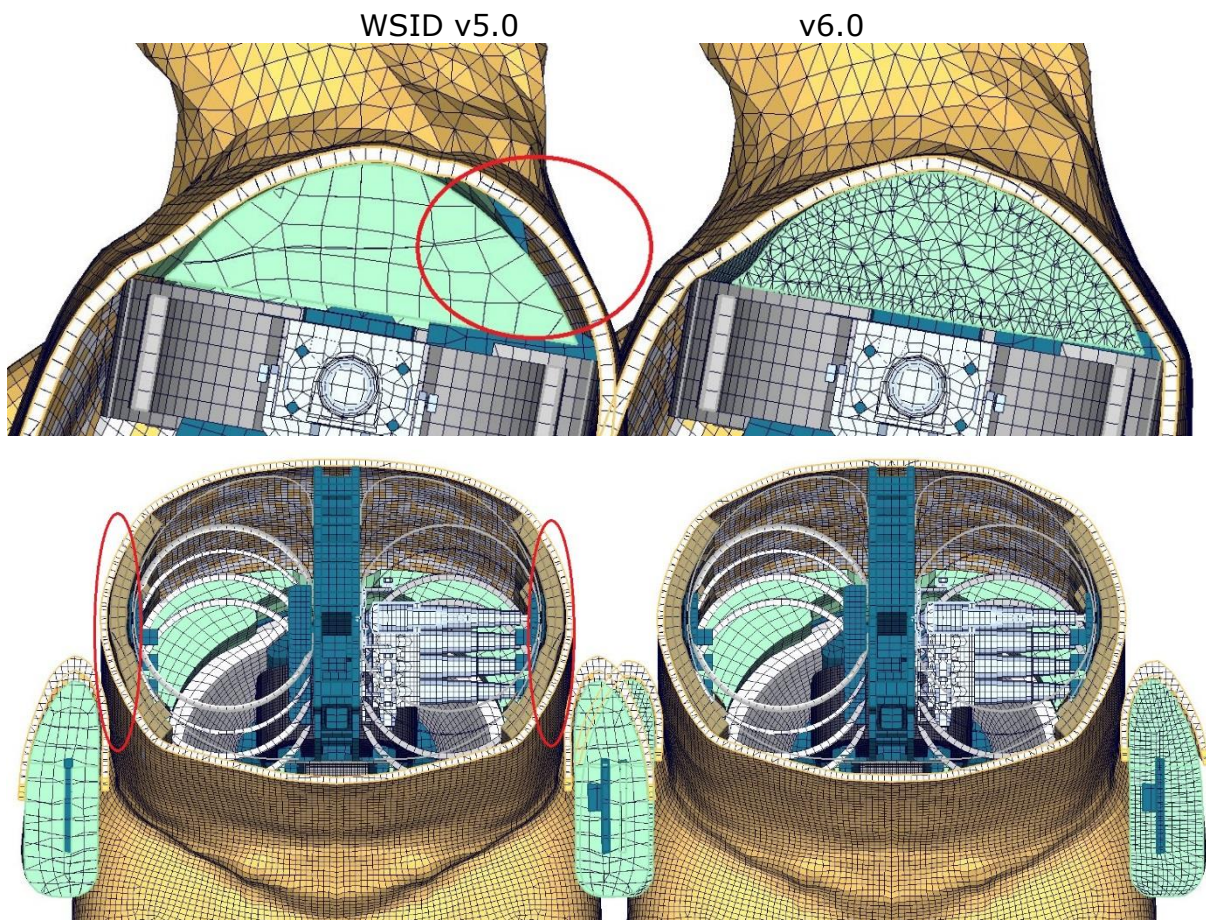
- Shoulder PAD geometric update



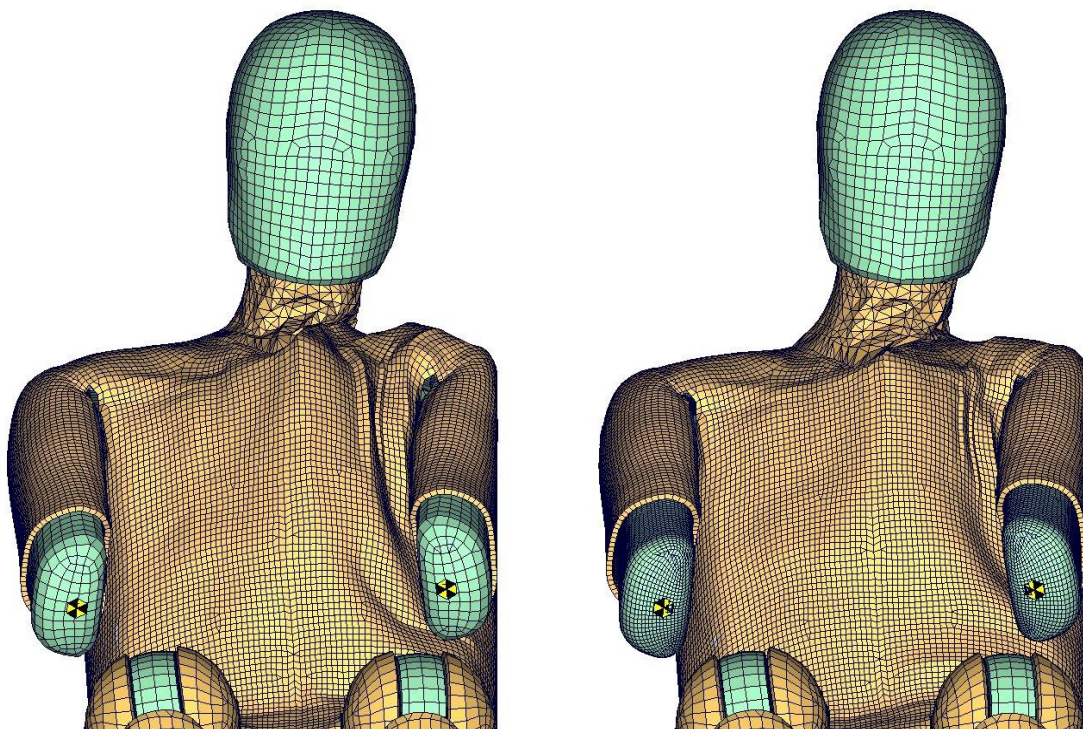
- New half arm has better deformation behavior in shoulder area. In the following a sled test is shown for both versions of WorldSID: Focus on the arm_joint hole



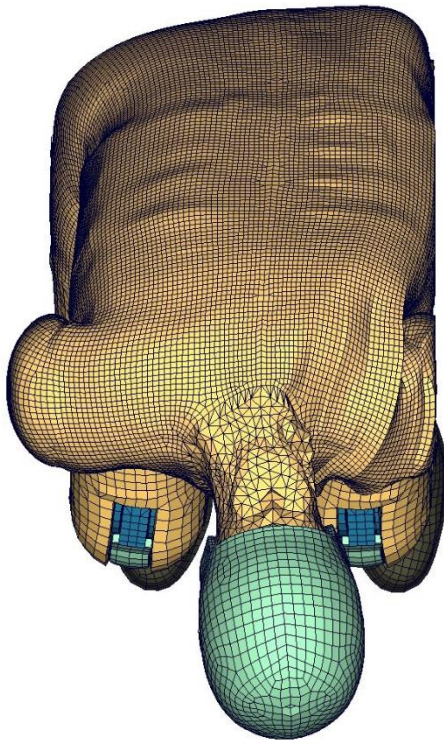
- Jacket is weared tight with initial stress.



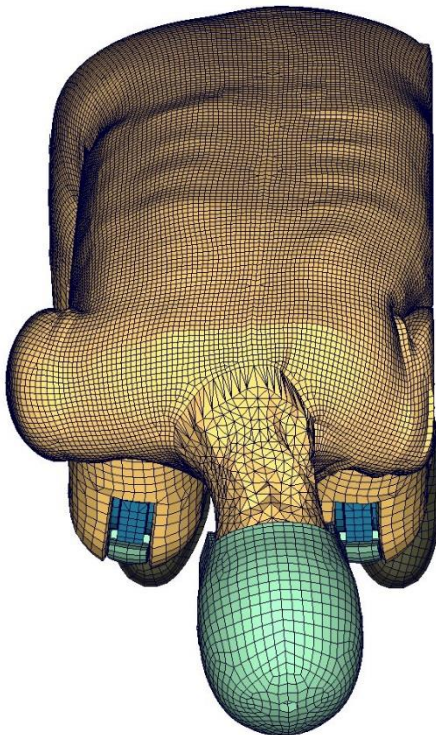
Jacket Performance in sled test: Flat barrier and arm second notch
WSID v5.0 v6.0



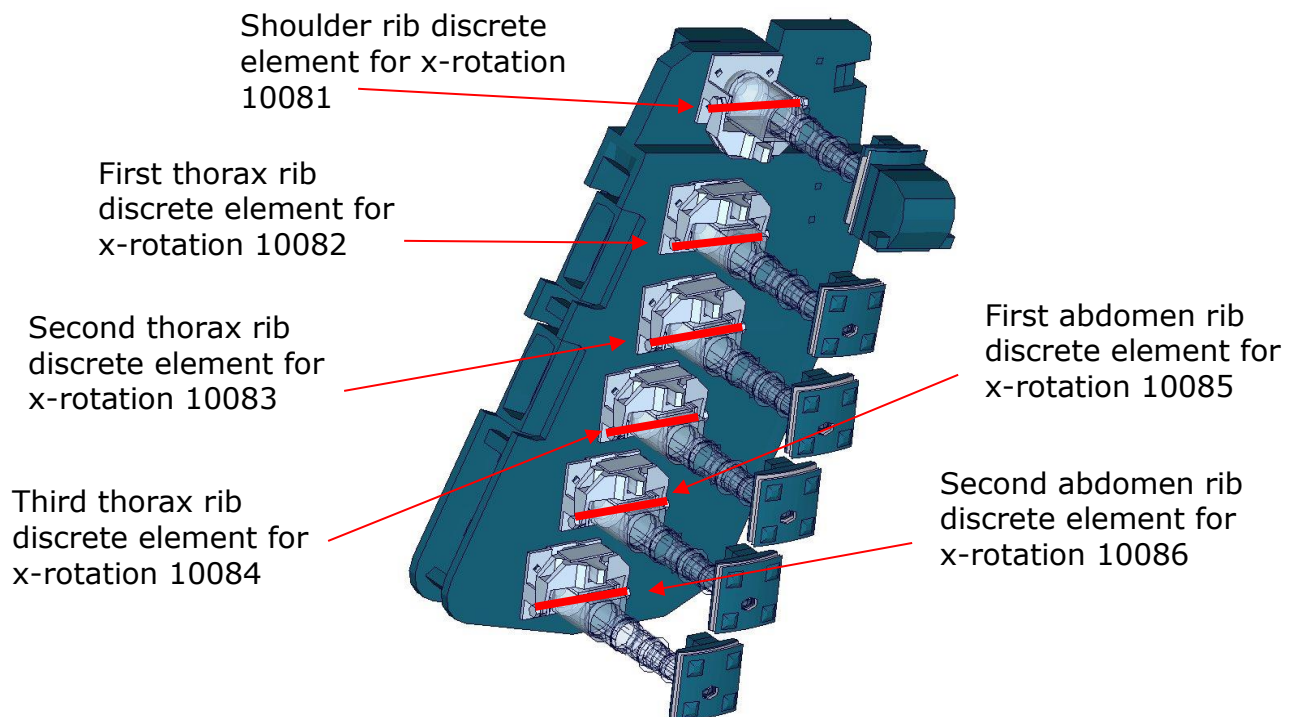
WSID v5.0



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:

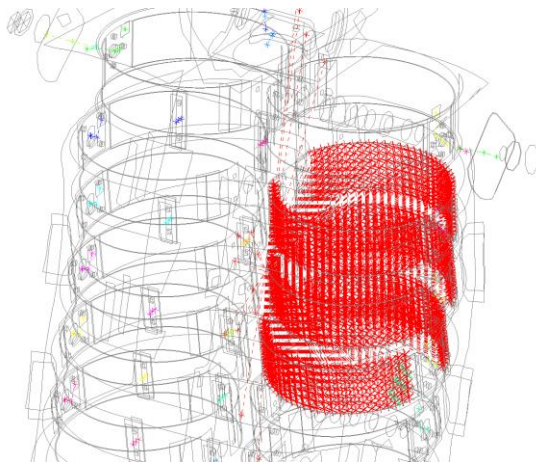
*CONSTRAINED_NODAL_RIGID_BODY

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

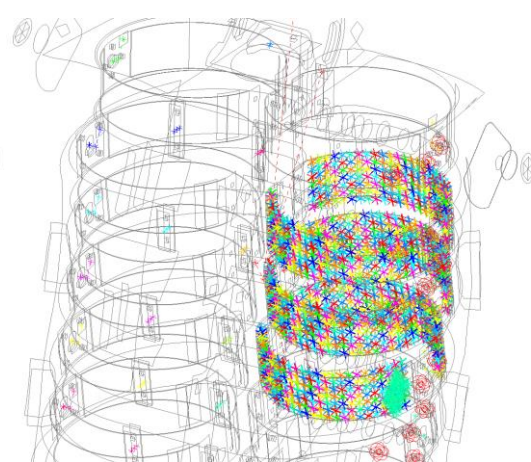
Update since version 6.0.1:

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



5.9 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.

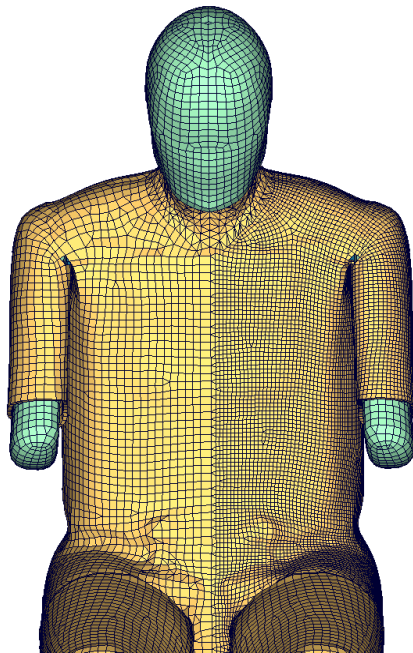
&trd_opt == 4: The thickness of thorax rib (Damp-MAT) is 4.35mm.

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

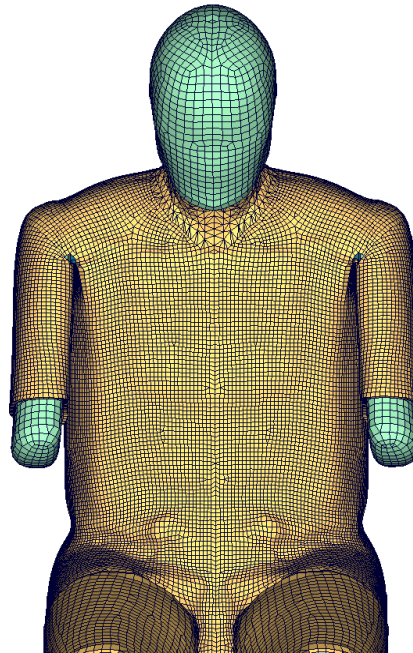
Very important comment: !!!!!

- 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.

WSID v4.0

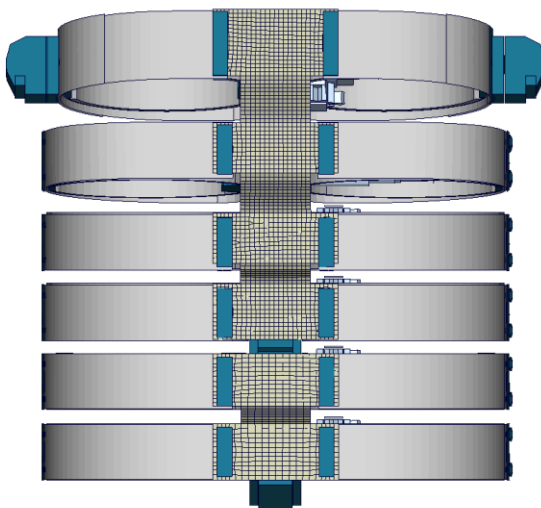


v5.0

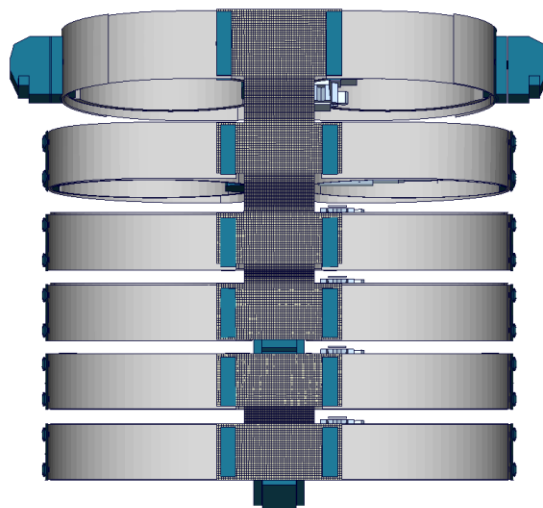


- Thorax rib coupler geometric update

WSID v4.0

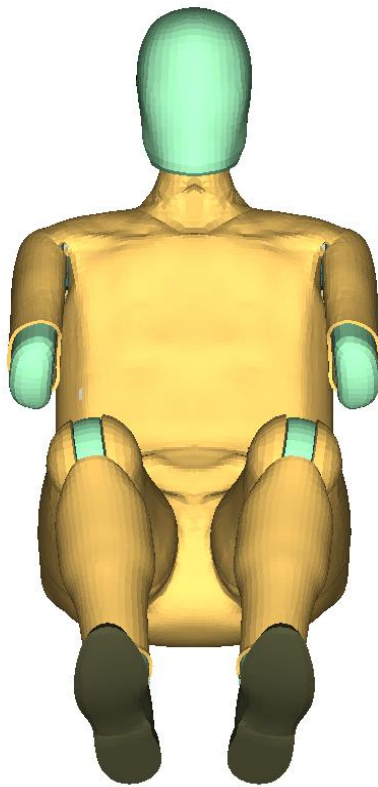


v5.0

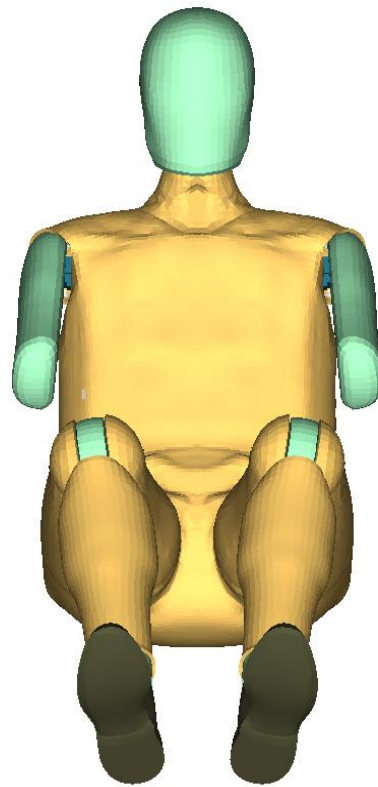


- Arm-sleeve is a include key-file in WorldSID v5.0. This can be switched very easy in dummy-key-file. Without arm-sleeve model is stander model for EuroNCAP Far-side test.

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



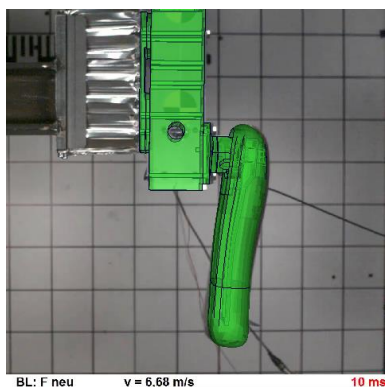
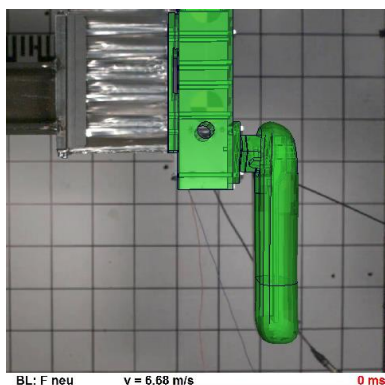
With arm-sleeve



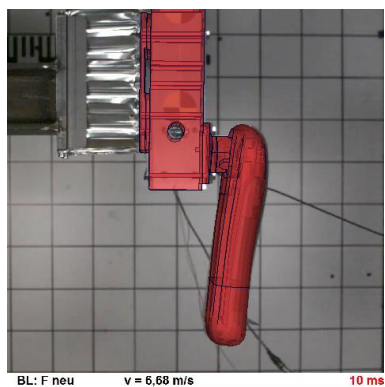
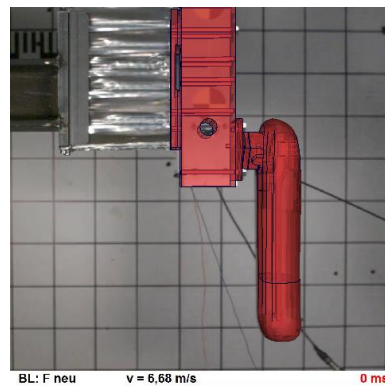
Without arm-sleeve

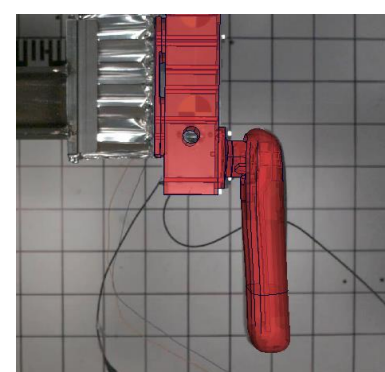
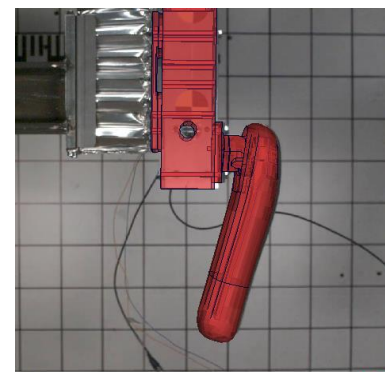
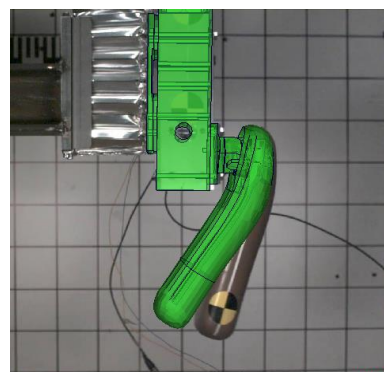
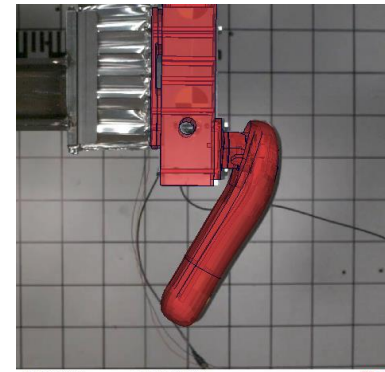
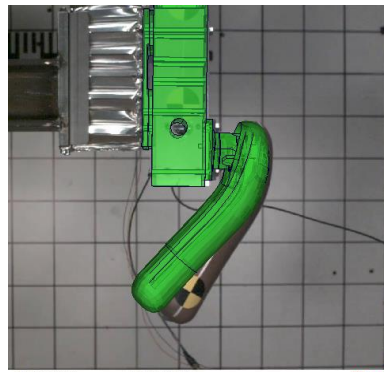
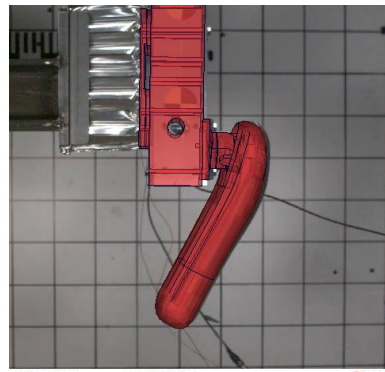
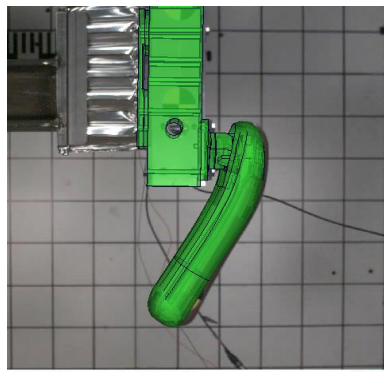
- Arm validation is improved. WSID v4.0 still has a relative soft half arm. The bending behavior of arm is improved in WSID v5.0. In the following a half-arm component test is shown for both versions of WorldSID:

WSID v4.0



v5.0





- ISO-CODE-Label are created for evaluation to instead of the old evaluation's label.
 - *DATABASE_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 right	THRIRI01WSAC
2. thorax rib	10022	accelerometer middle thorax rib right	THRIRI02WSAC
3. thorax rib	10023	accelerometer lower thorax rib right	THRIRI03WSAC
1. abdomen rib	10024	accelerometer upper abdomen rib right	ABRIRI01WSAC
2. abdomen rib	10025	accelerometer lower abdomen rib right	ABRIRI02WSAC
Tibia	10101	accelerometer tibia left	TIBILE00WSAC
Tibia	10102	accelerometer tibia right	TIBIRI00WSAC

- *DATABASE_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 cell	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

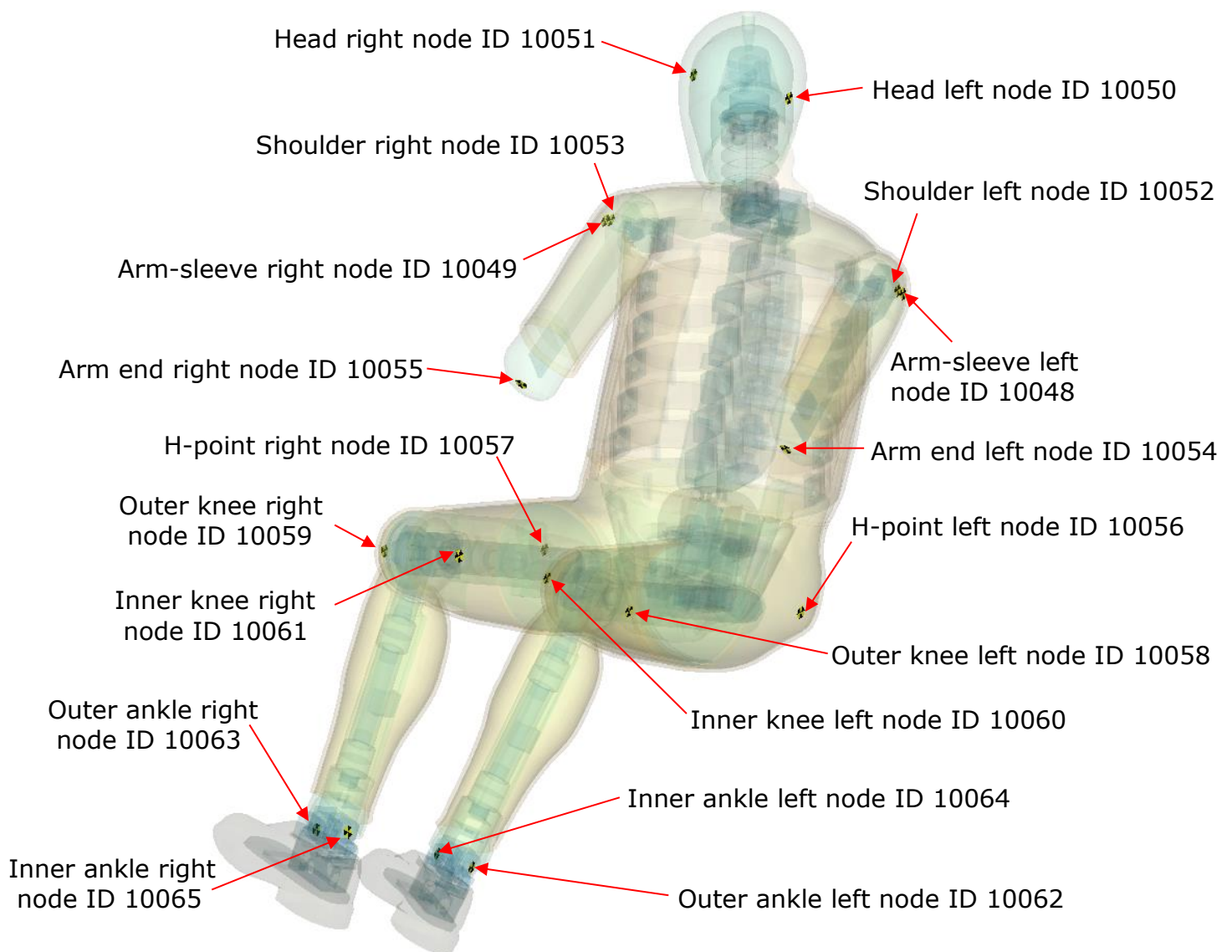
Femoral neck load cell left hand side	10008	femoral neck load cell left	FEACLE00WS
Femoral neck load cell right hand side	10009	femoral neck load cell right	FEACRI00WS
Femur load cell left hand side	10010	femur load cell left	FEMRLE00WS
Femur load cell right hand side	10011	femur load cell right	FEMRRI00WS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

- *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 deformation	10064	no label	ABRILE01WSDS0
2. abdomen rib deformation	10065	no label	ABRILE02WSDS0
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-rotation left	10040	no label	KNEELE00WSANY
knee potentiometer y-rotation right	10041	no label	KNEERI00WSANY
ankle potentiometer z-rotation left	10042	no label	ANKLLE00WSANZ
ankle potentiometer z-rotation right	10043	no label	ANKLRI00WSANZ

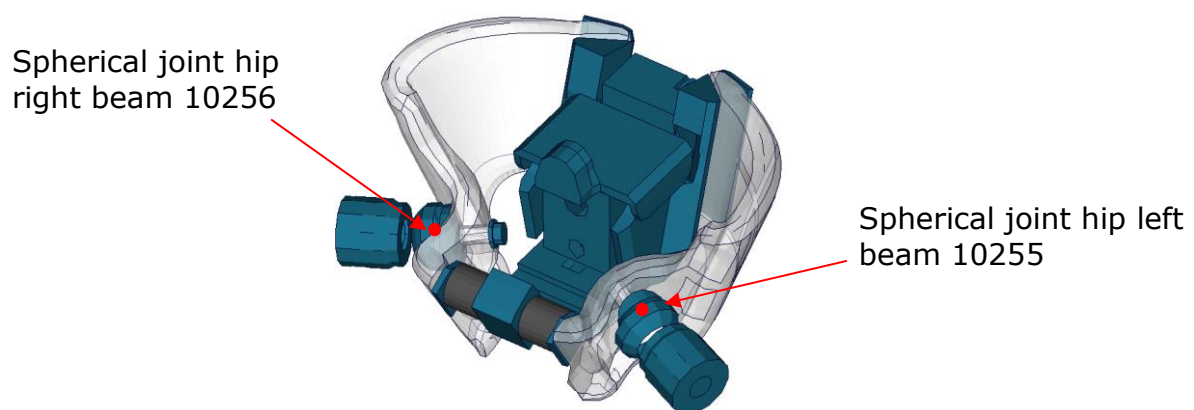
ankle potentiometer y-rotation left	10044	no label	ANKLLE00WSANY
ankle potentiometer y-rotation right	10045	no label	ANKLRI00WSANY
ankle potentiometer x-rotation left	10046	no label	ANKLLE00WSANX
ankle potentiometer x-rotation right	10047	no label	ANKLRI00WSANX

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



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 right	10065	ANKLRIMIWSAC	global node output

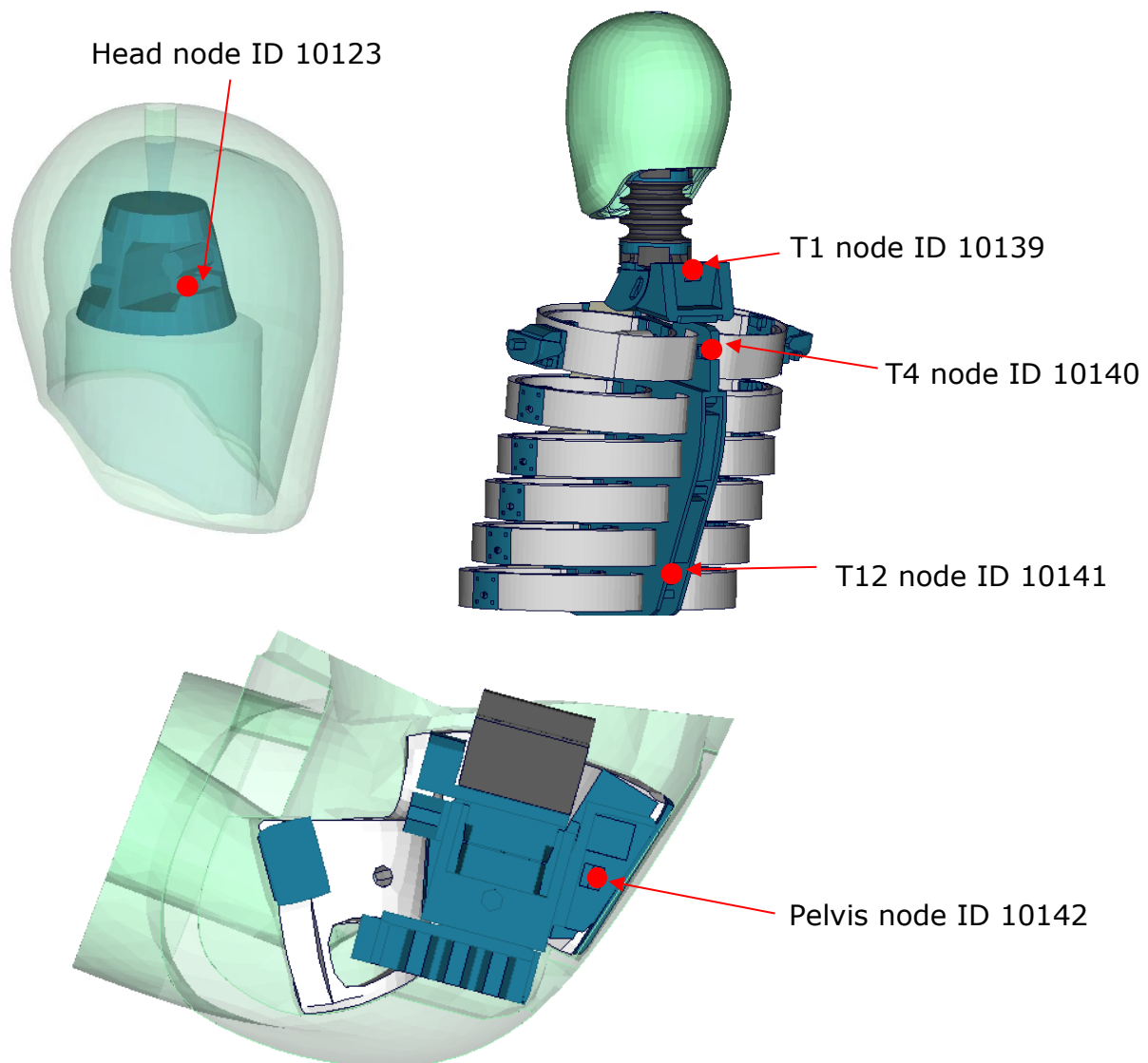
- The global force of the spherical joint hip left and right are new force and moment signals for WorldSID v5.0 in global coordinate system by beam 10255 and 10256.



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

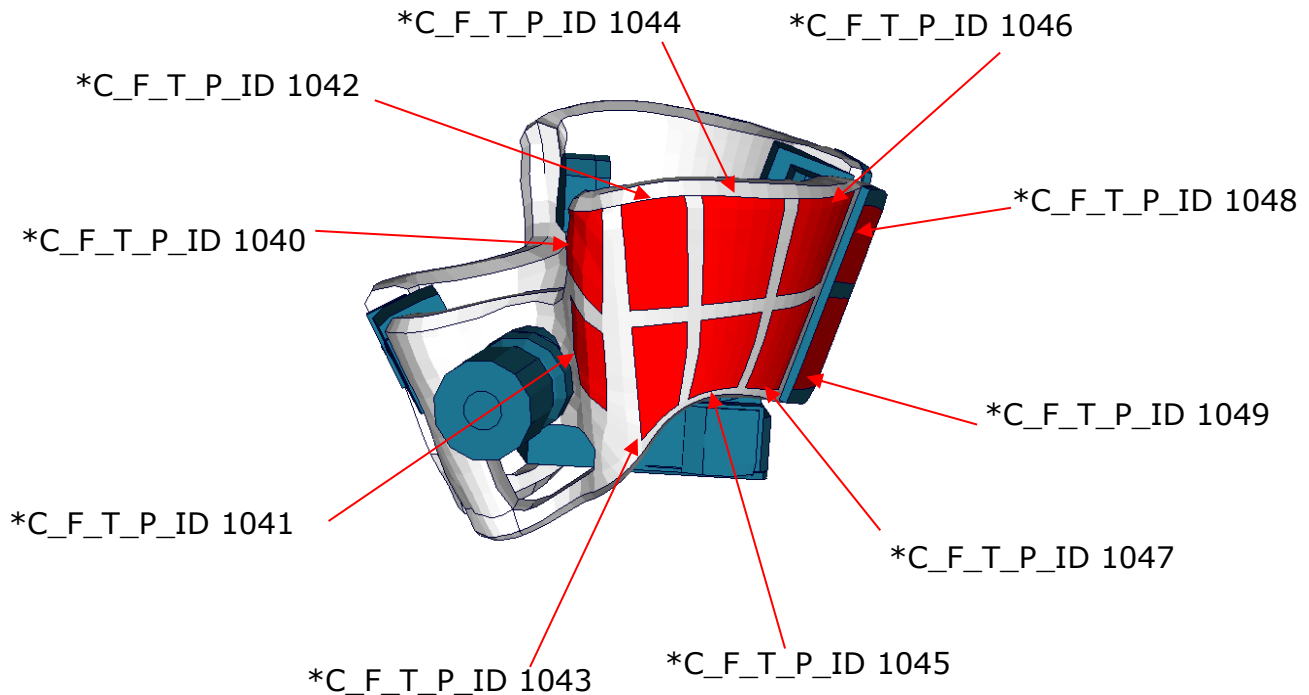
The `CONSTRAINED_JOINT_STIFFNESS_TRANSLATIONAL` cards IDs are as follows:

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

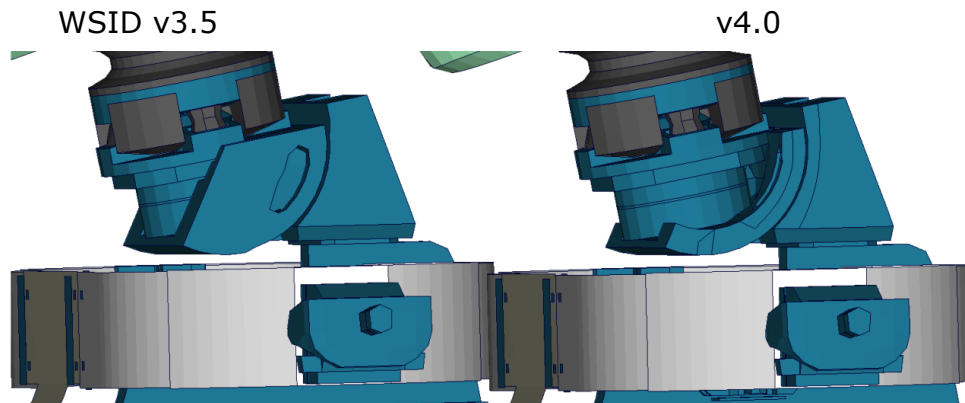


The * CONTACT_FORCE_TRANSDUCER_PENALTY_ID list:

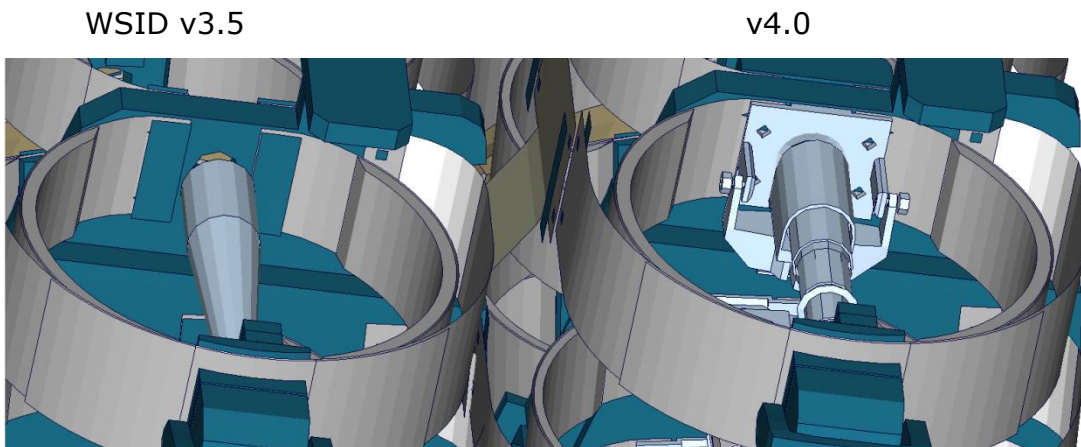
Item	C_F_T_P_ID	Label	Available components
Pelvis Force	1040	pelvis bone force left - upper front	global contact force x-,y-,z-, resultant ;
Pelvis Force	1041	pelvis bone force left - lower front	global contact force x-,y-,z-, resultant ;
Pelvis Force	1042	pelvis bone force left - upper side forward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

5.10 Release notes of WorldSID v4.0

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



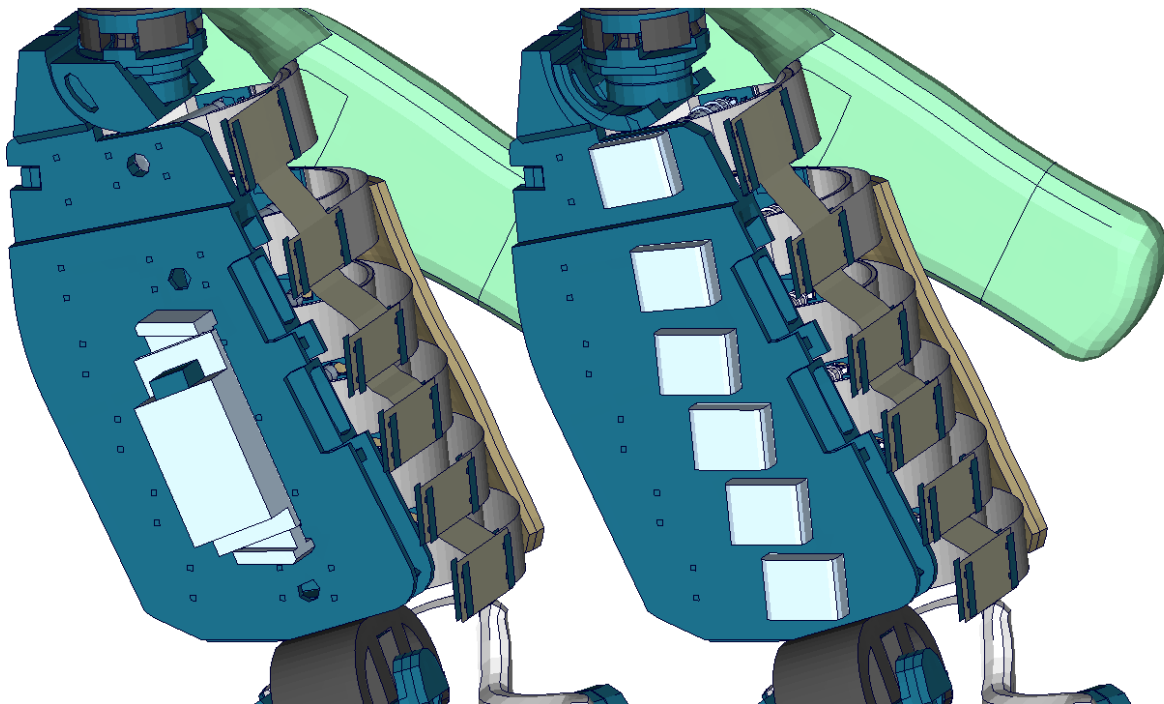
- Update of 2D IR-TRACC geometry. Due to this the physical stop angles are captured much more accurate.



- Battery in thorax has been changed to some smaller mass replacements

WSID v3.5

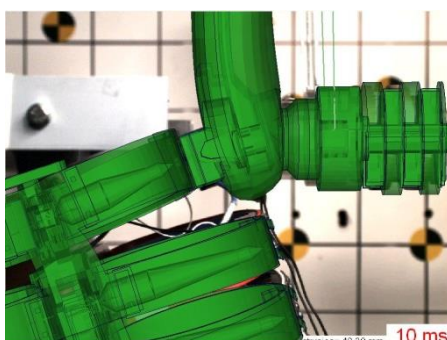
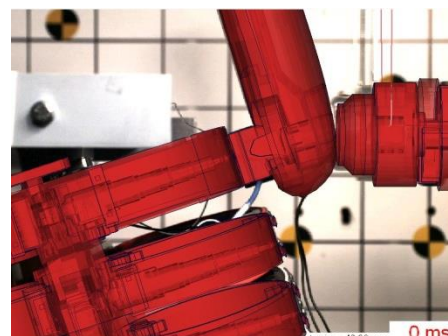
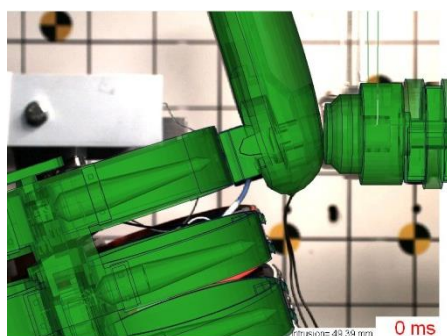
v4.0

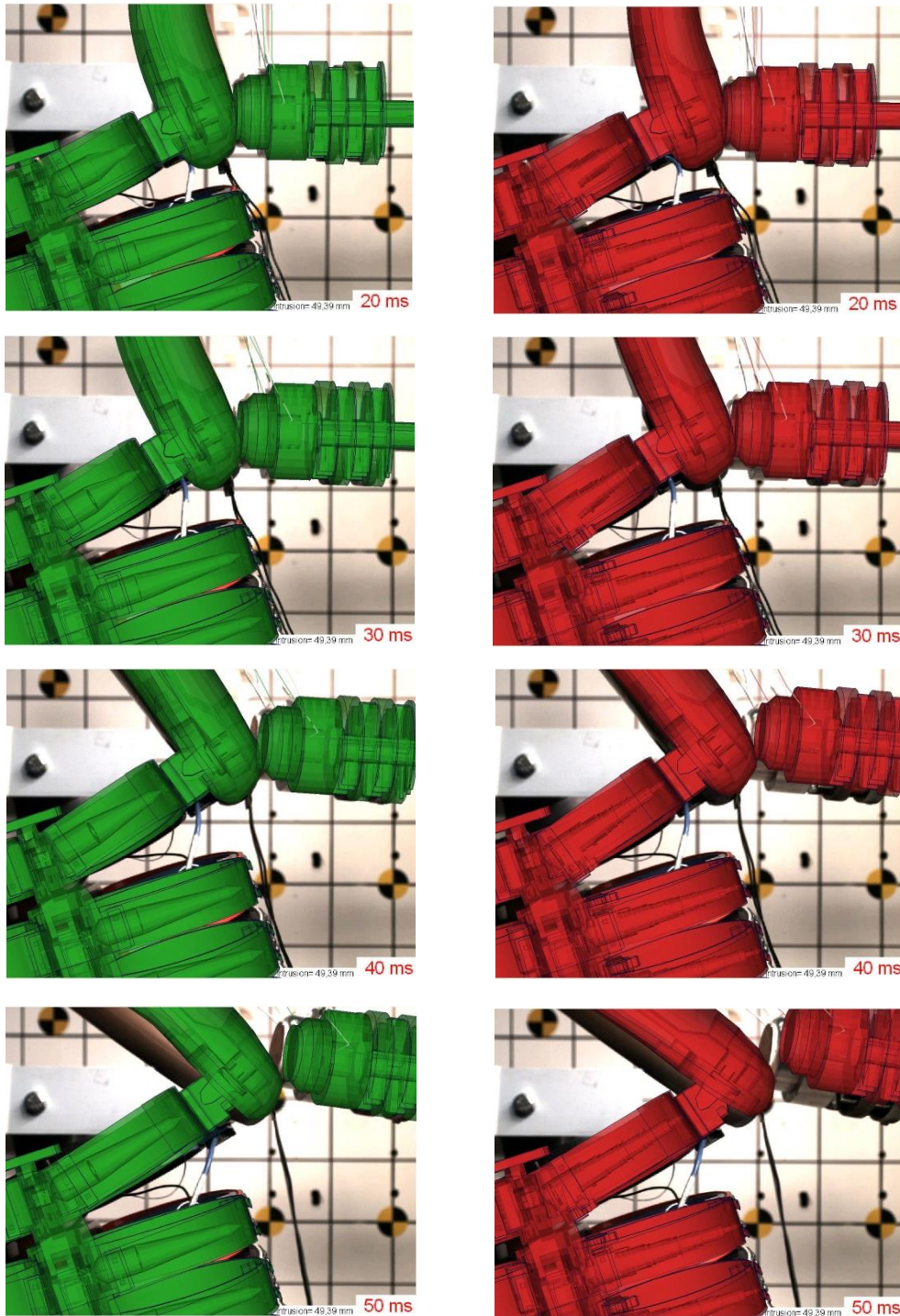


- Other modifications:
 - Arm validation is improved. In some Rib component test it is observed that WSID v3.5 seems to have a very soft arm behavior in bending. Due to this the behavior of the arm is compared to video evaluations and improved. In the following a rib component test with arm is shown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

WSID v3.5

v4.0





- 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.

The nodes are:

Item	Node-ID	Label	Available components
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

- 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 bye springs 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

5.11 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 done due to positioning issues with the psg of the WorldSID50.
- Other modifications:
 - 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.

5.12 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 `*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
- Improvement of the hole dummy definitions to reduce time step dependency of the model
- 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

5.13 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 z-direction. 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.

5.14 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 ins 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.

The thorax calibration simulation is with a new contact face pendulum. But the test data are still with the old pendulum. For the next release, we are going to collect the new thorax calibration test data and also continue to improve the model performance.

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
- lumbar 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	Type	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 39: 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
- Neck Torsion
- Half arm
- Arm Bending
- Arm Joint test
- Different ribs of the thorax and abdomen
- Lumbar spine
- Iliac wing

Head-neck include old test and VTC test, old test is shown in this user manual, VTC test is shown in VTC report.

Lumbar spine include old test and VTC test, old test is not suitable since version 8.0.

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.

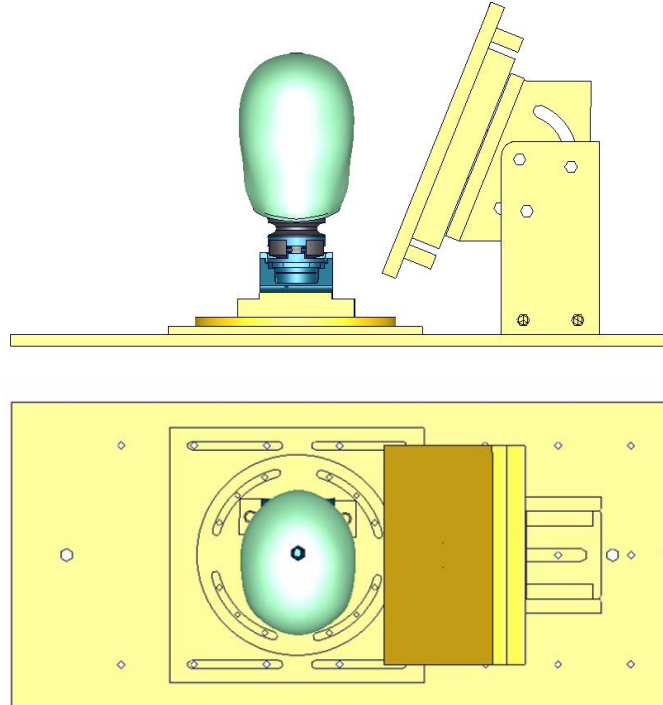


Figure 31: Head-neck test setup - 90 degree, side and top view

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 40: Test configurations of head-neck test

Results of 90 degree, 20g configuration:

Head accelerometer

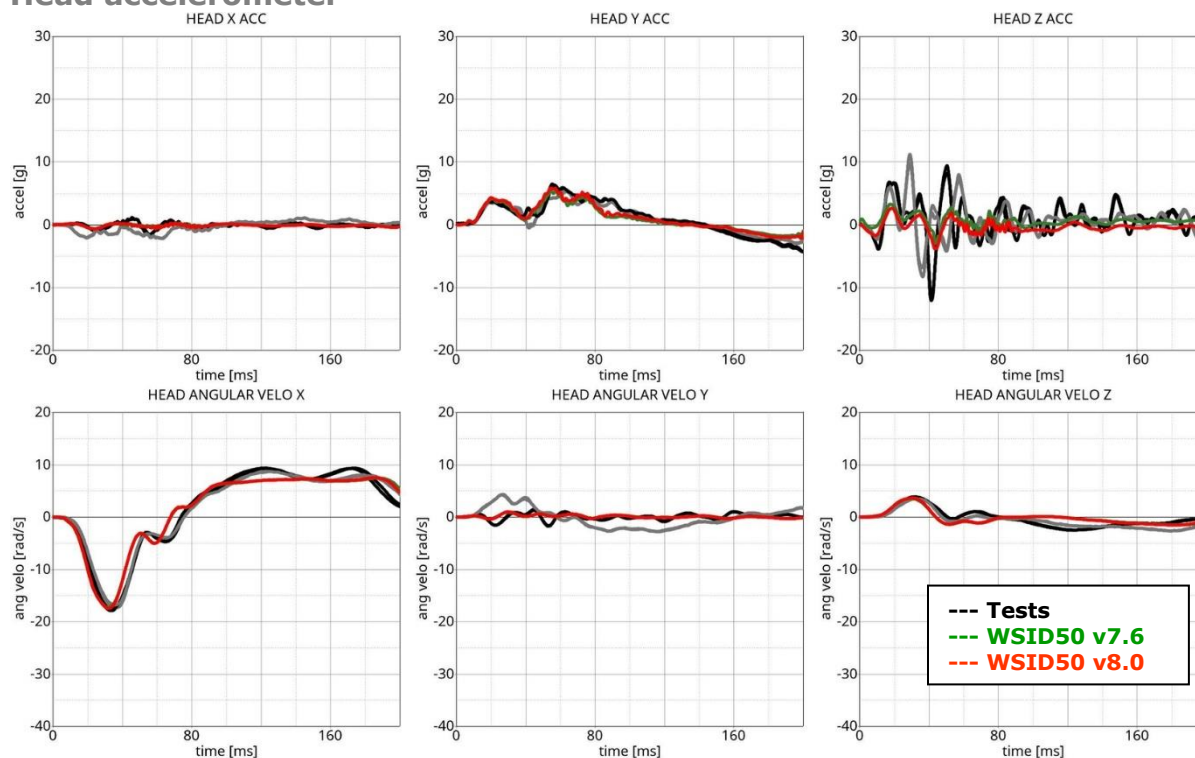


Figure 32: Result of head-neck test -- 20g, 90 degree (Head acceleration)

Upper neck load cell

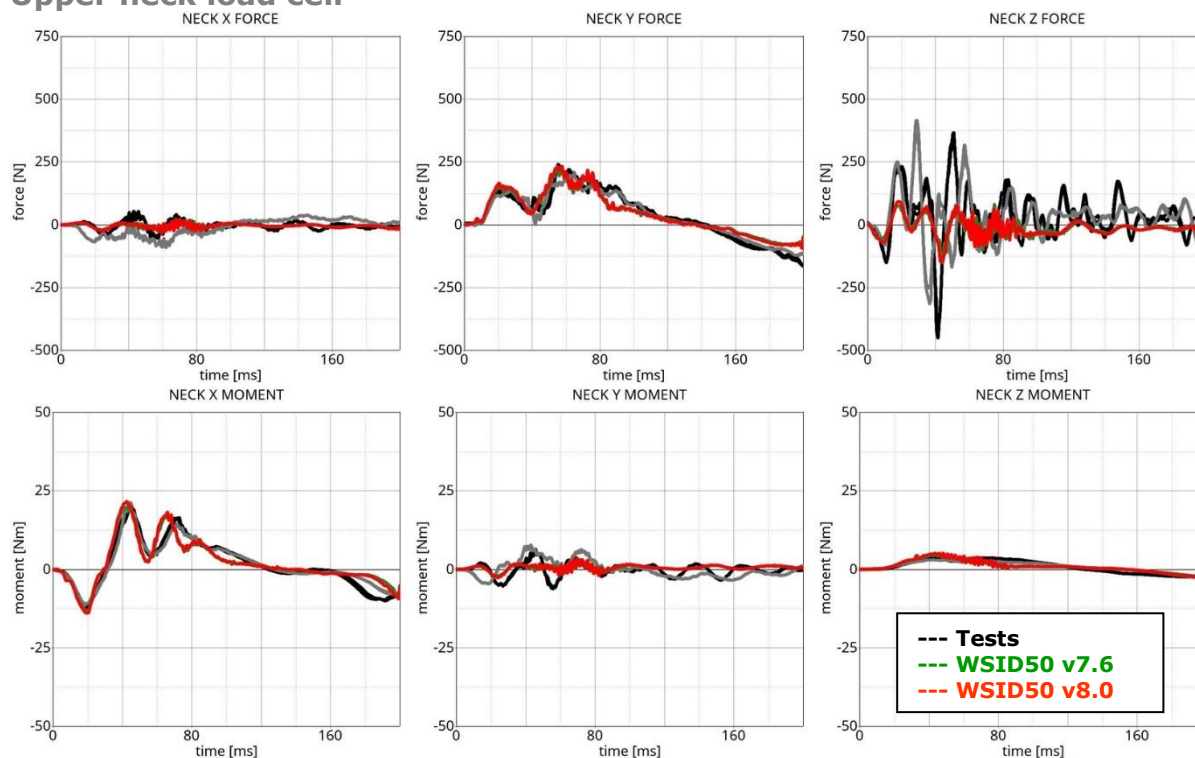


Figure 33: Result of head-neck test -- 20g, 90 degree (Upper neck forces and moments)

Lower neck load cell

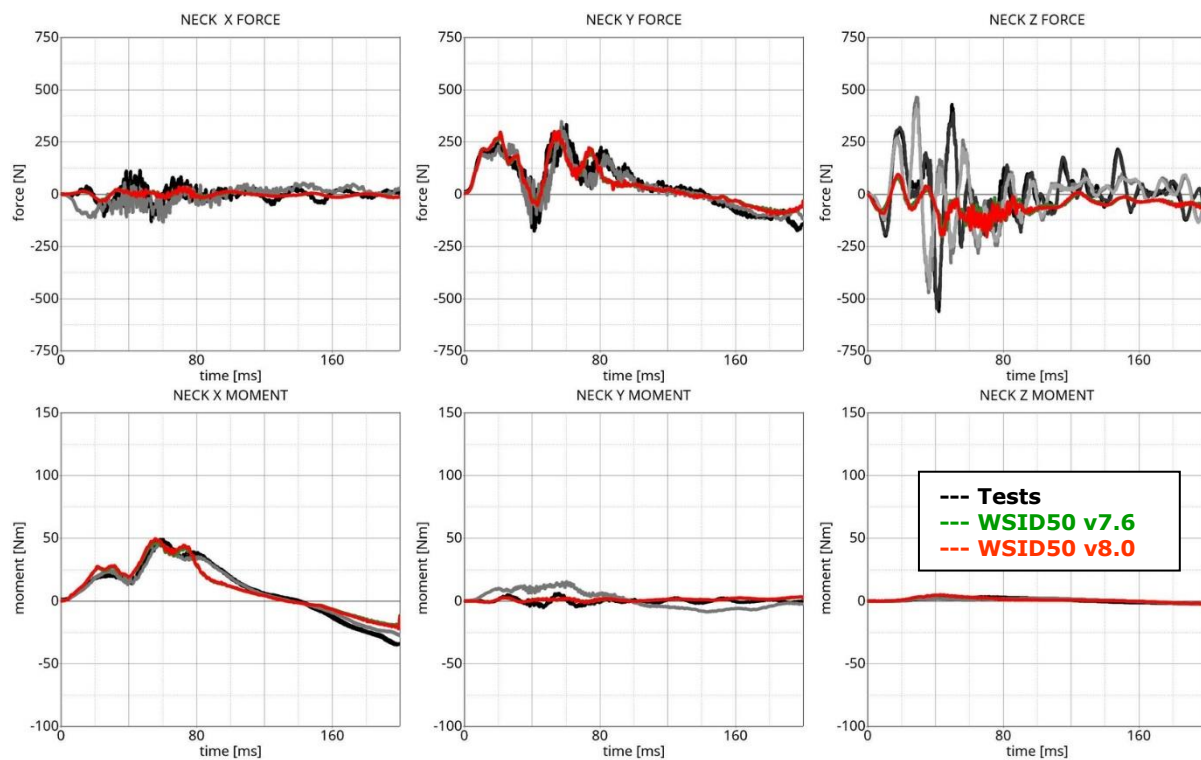


Figure 34: Result of head-neck test -- 20g, 90 degree (Lower neck forces and moments)

Results of 90 degree, 35g configuration:

Head accelerometer

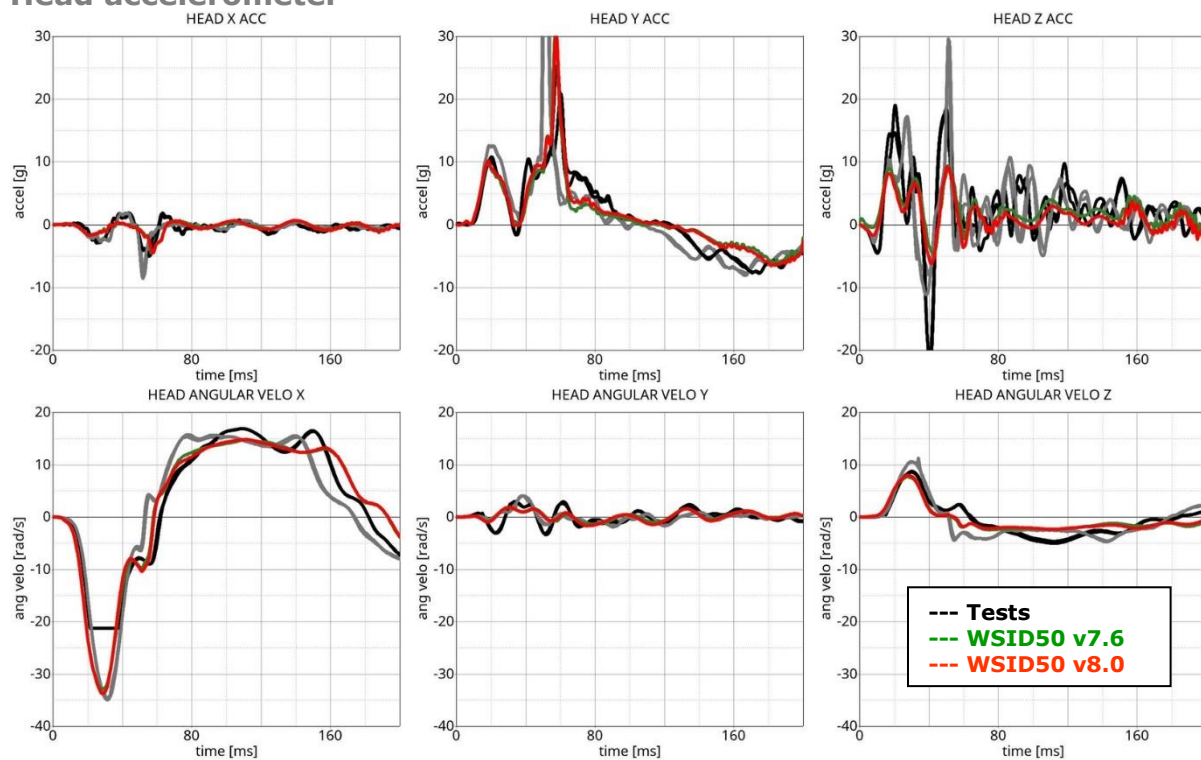


Figure 35: Result of head-neck test -- 35g, 90 degree (Head acceleration)

Upper neck load cell

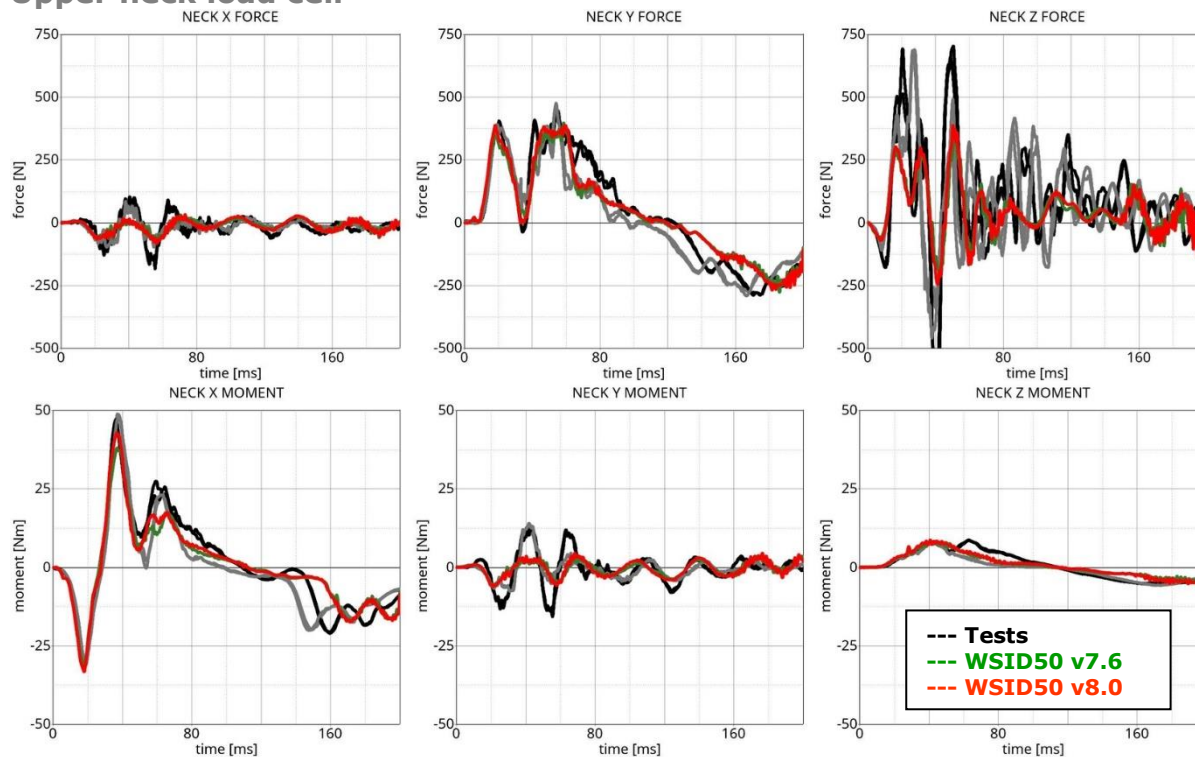


Figure 36: Result of head-neck test -- 35g, 90 degree (Upper neck forces and moments)

Lower neck load cell

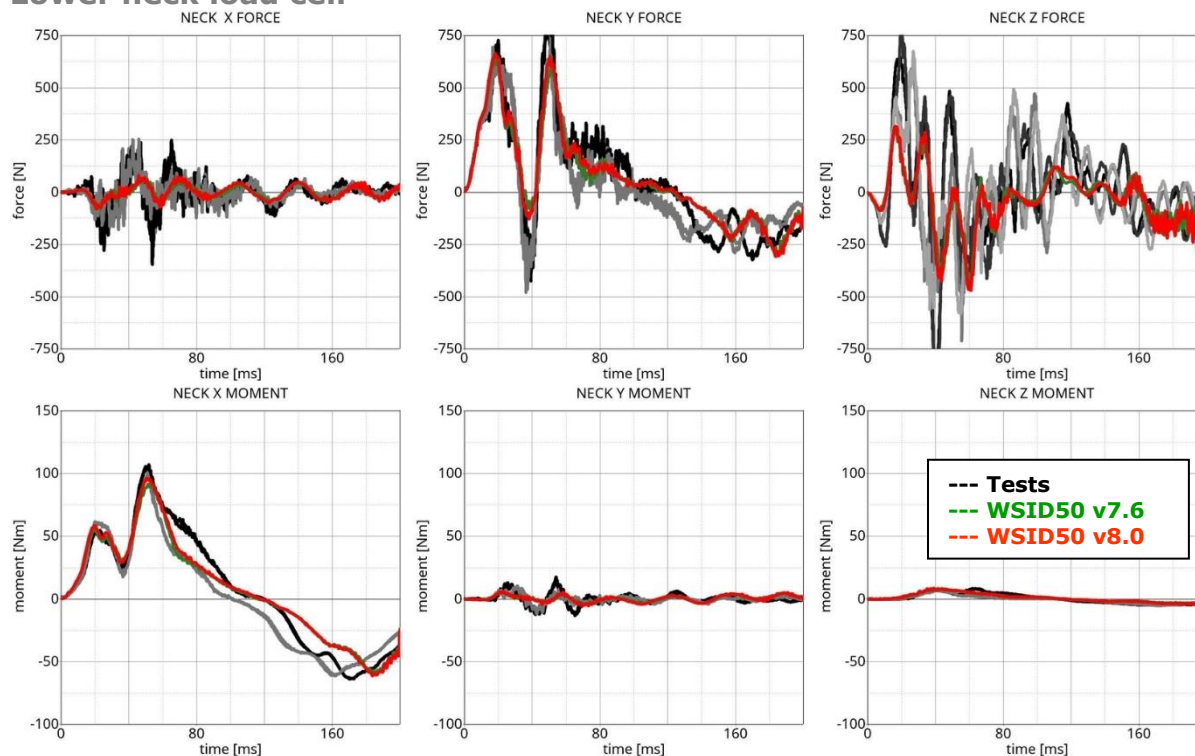


Figure 37: Result of head-neck test -- 35g, 90 degree (Lower neck forces and moments)

Results of 75 degree, 20g configuration:

Head accelerometer

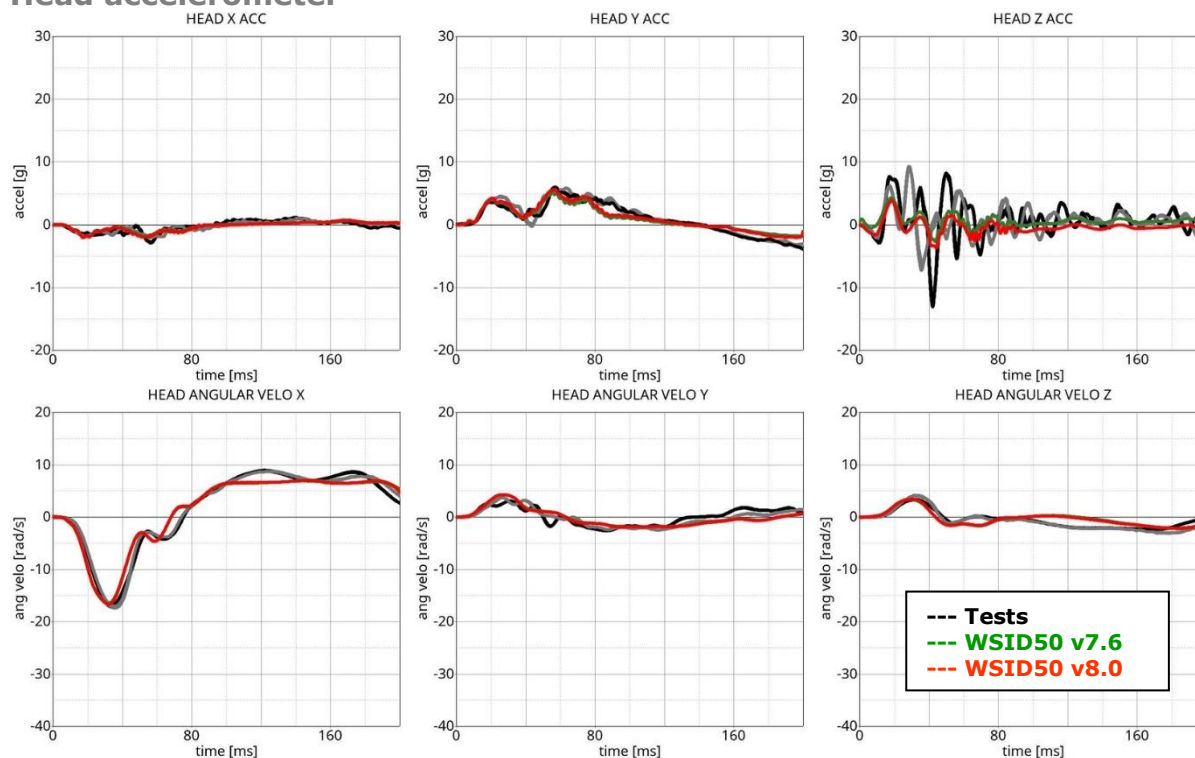


Figure 38: Result of head-neck test -- 20g, 75 degree (Head acceleration)

Upper neck load cell

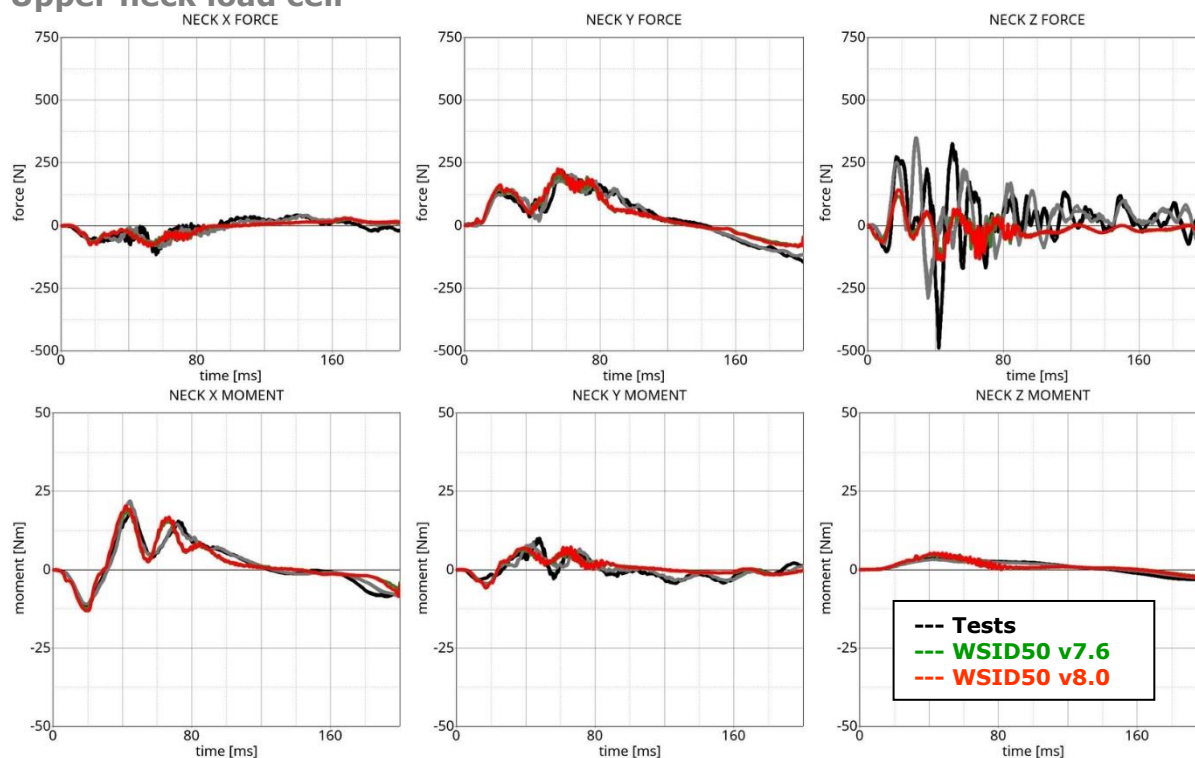


Figure 39: Result of head-neck test -- 20g, 75 degree (Upper neck forces and moments)

Lower neck load cell

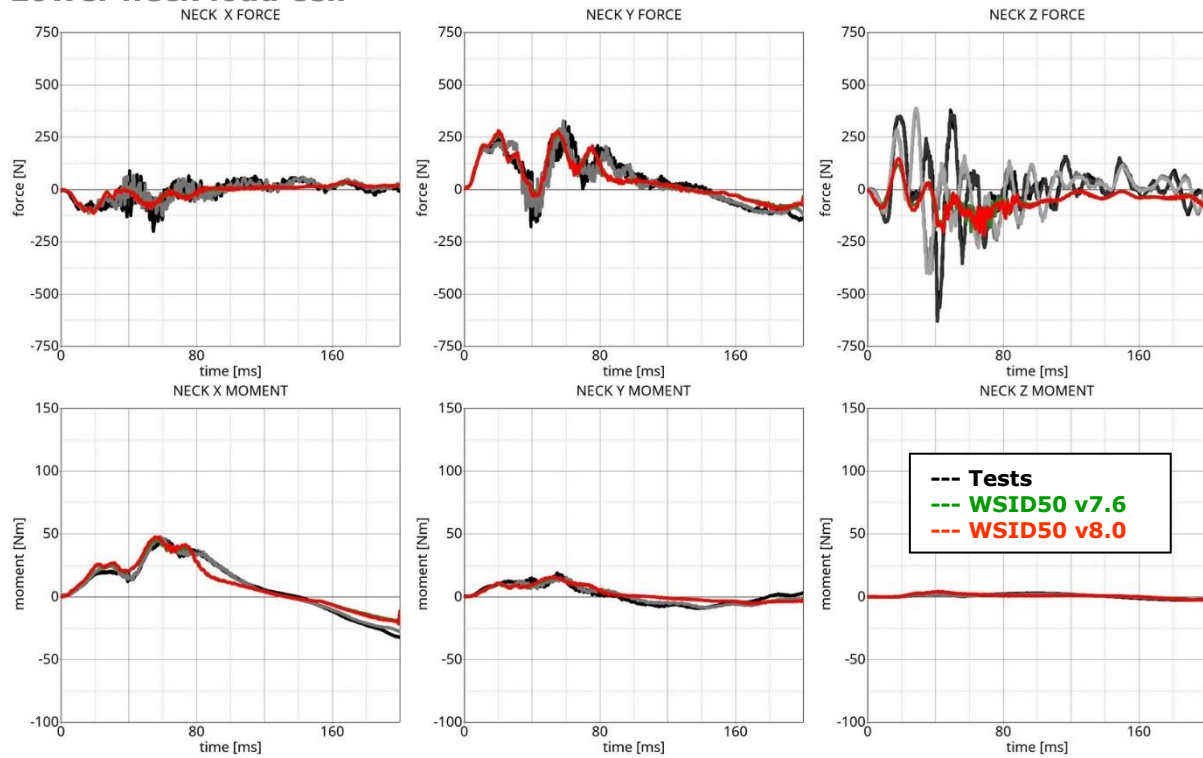


Figure 40: Result of head-neck test -- 20g, 75 degree (Lower neck forces and moments)

Results of 75 degree, 35g configuration:

Head accelerometer

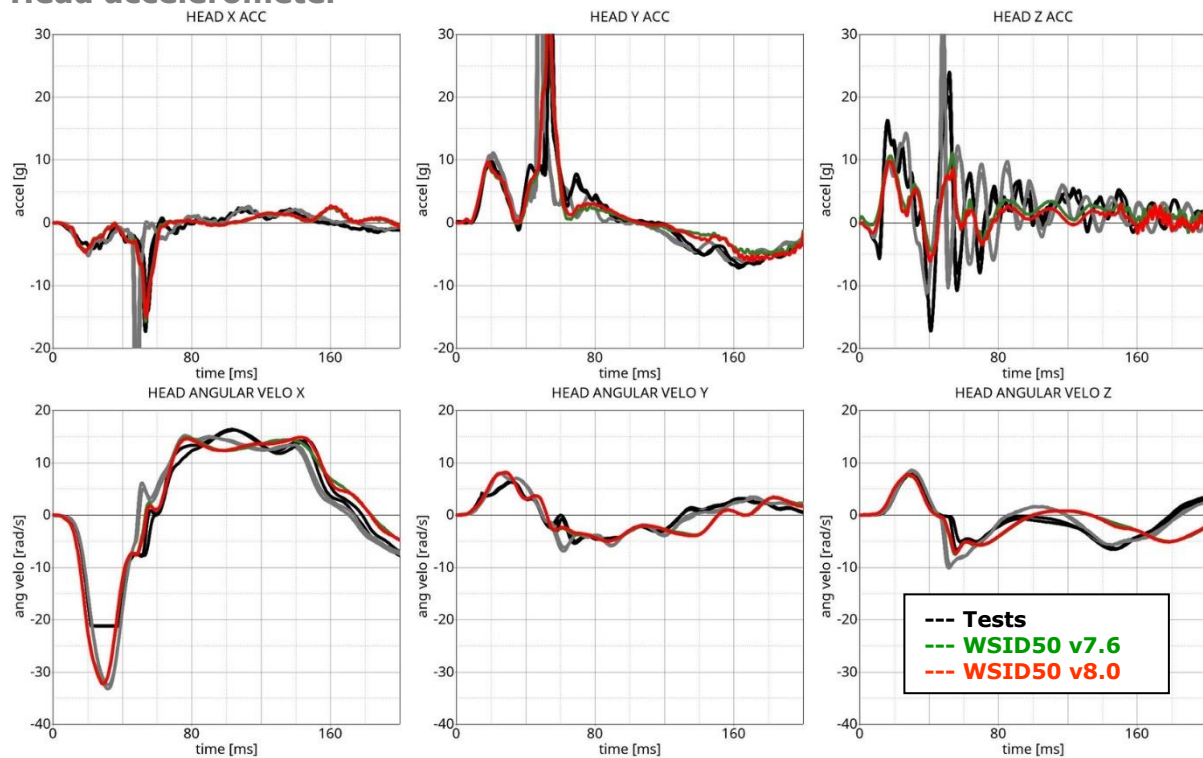


Figure 41: Result of head-neck test -- 35g, 75 degree (Head acceleration)

Upper neck load cell

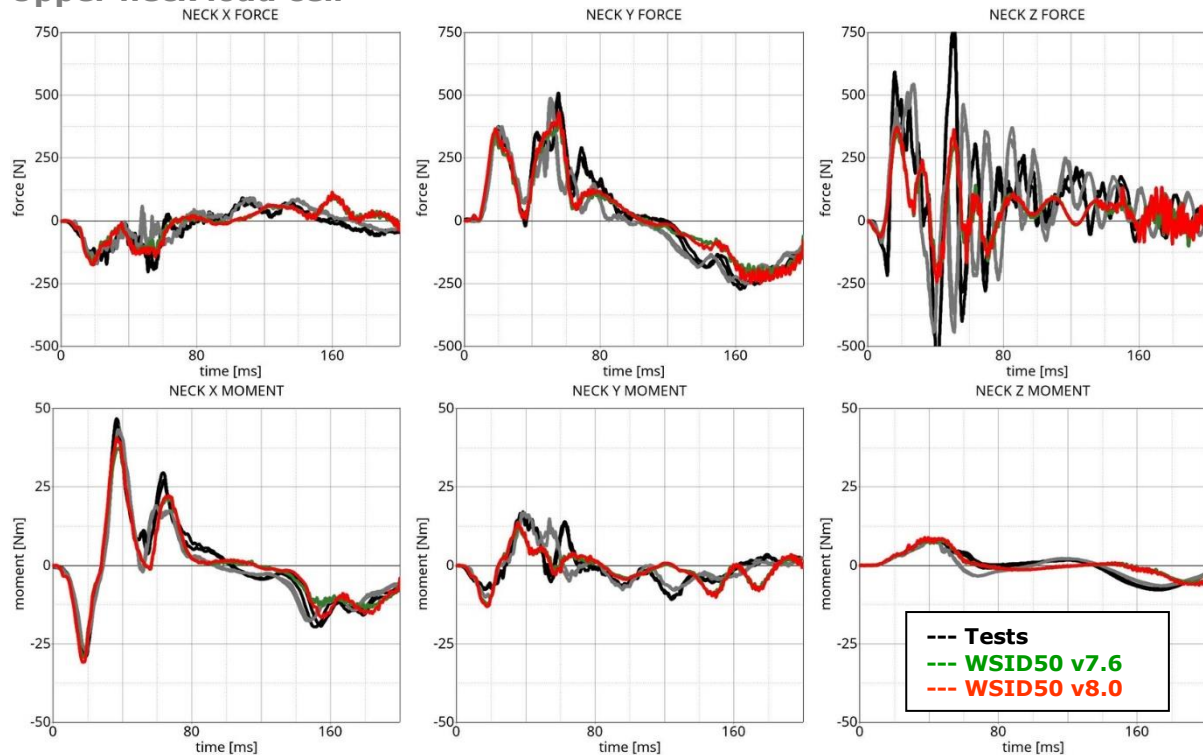


Figure 42: Result of head-neck test -- 35g, 75 degree (Upper neck forces and moments)

Lower neck load cell

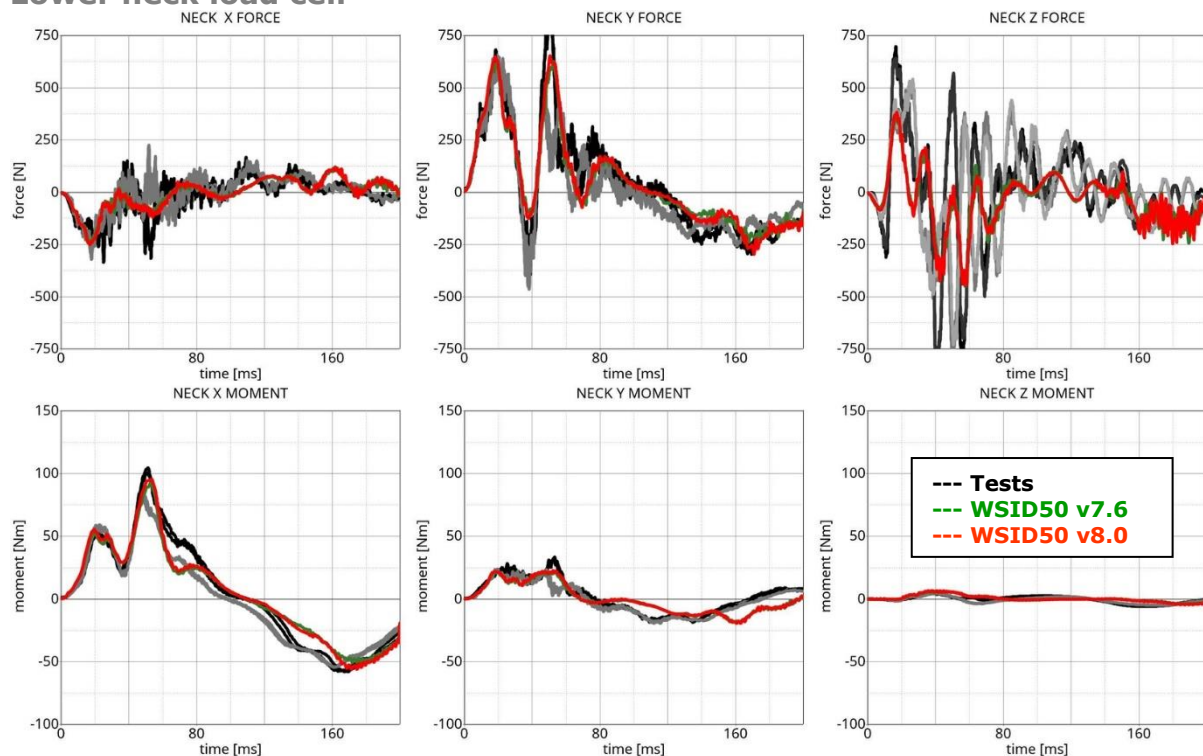


Figure 43: Result of head-neck test -- 35g, 75 degree (Lower neck forces and moments)

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.

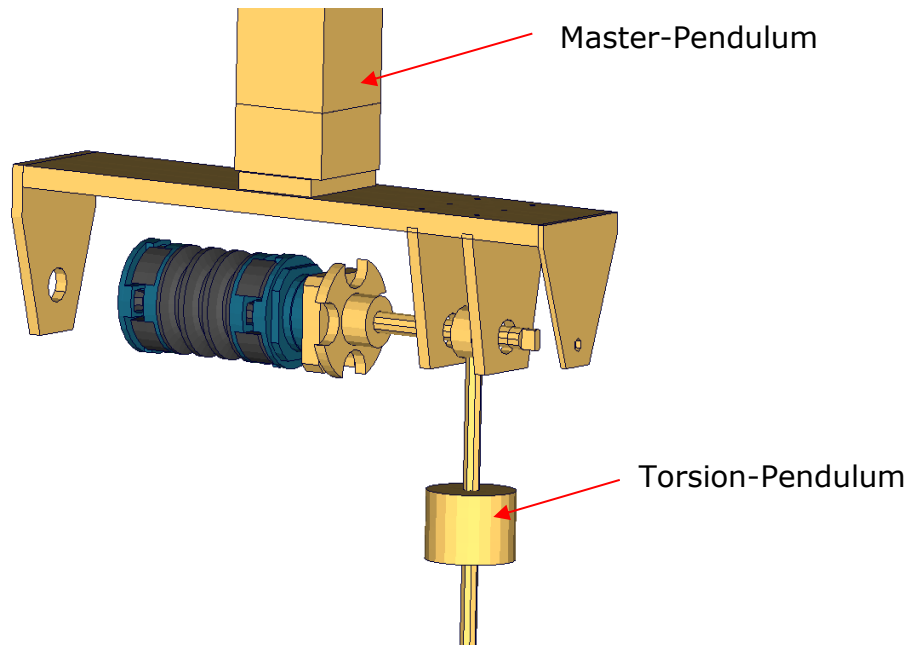


Figure 44: Neck Torsion test setup with pendulum

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

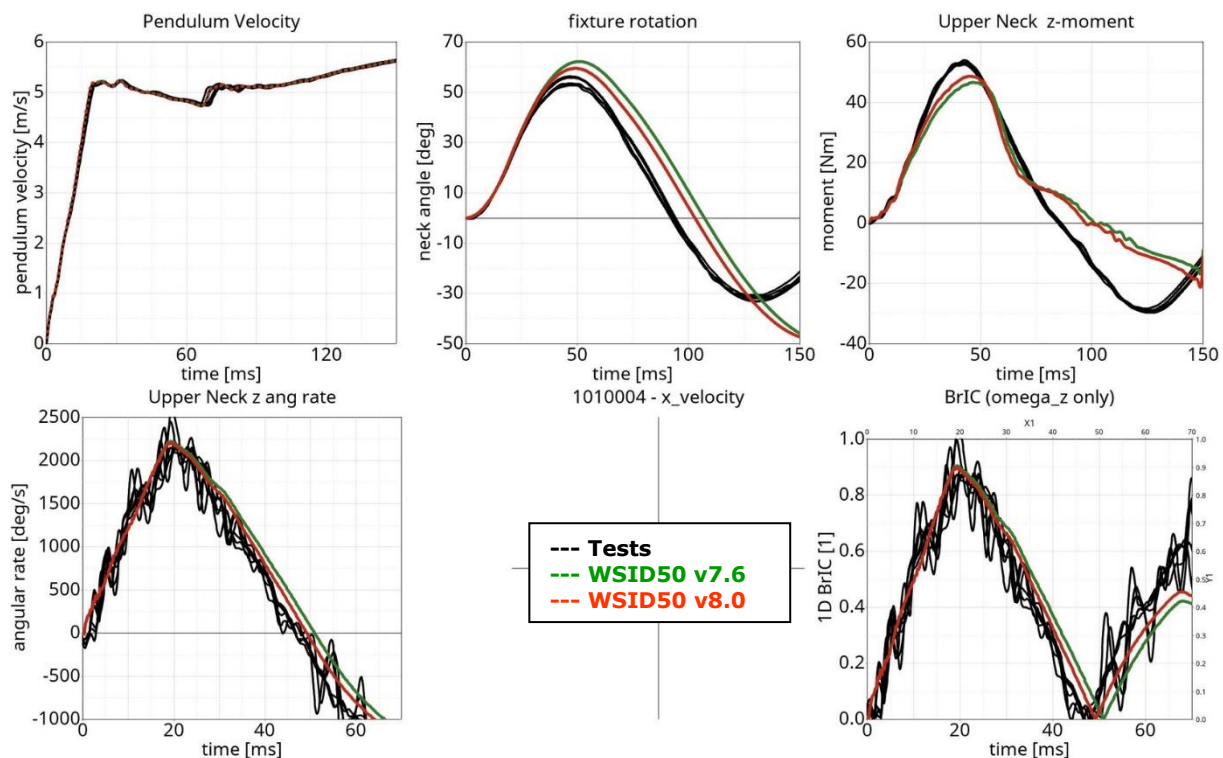


Figure 45: Results – Neck Torsion test

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 41 all test setup configurations are listed.

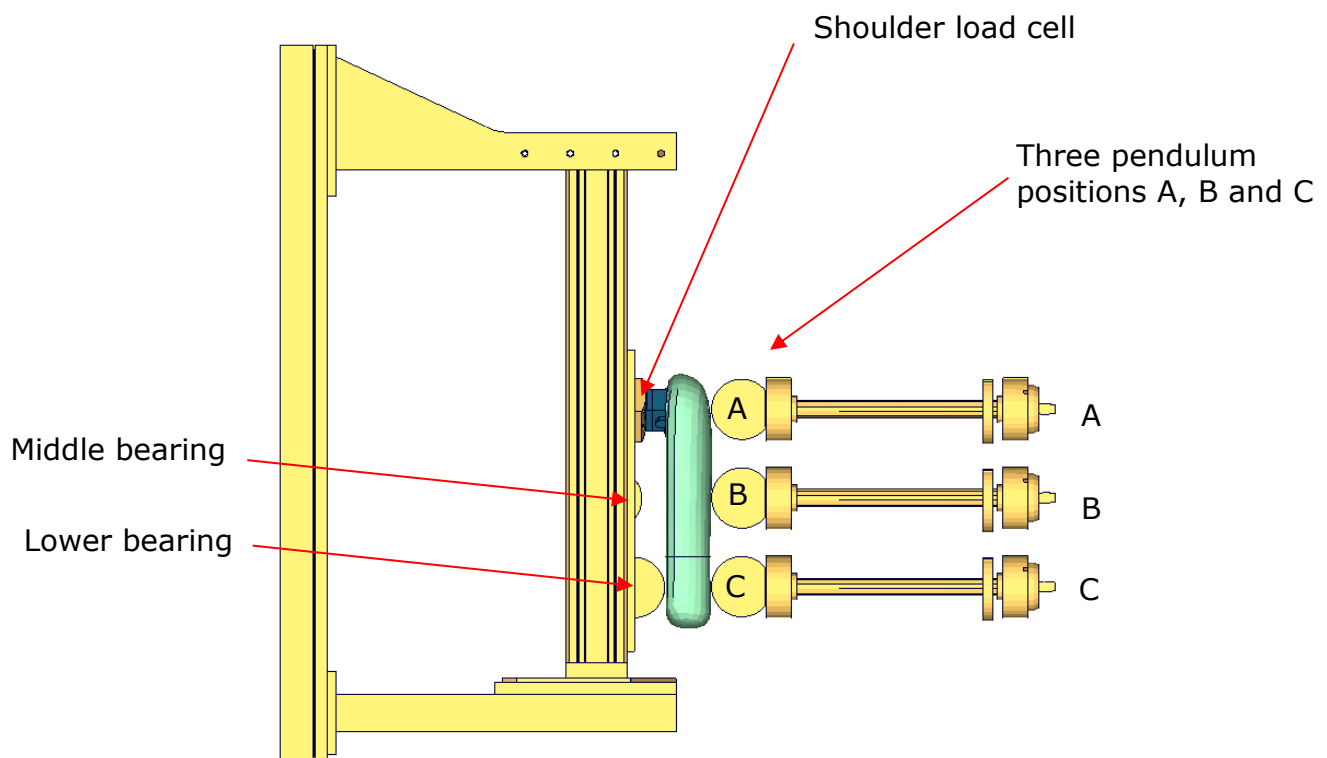


Figure 46: Half arm test setup with all pendulum positions

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

Table 41: Test configurations 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, 2 m/s velocity, 48 degree load cell position

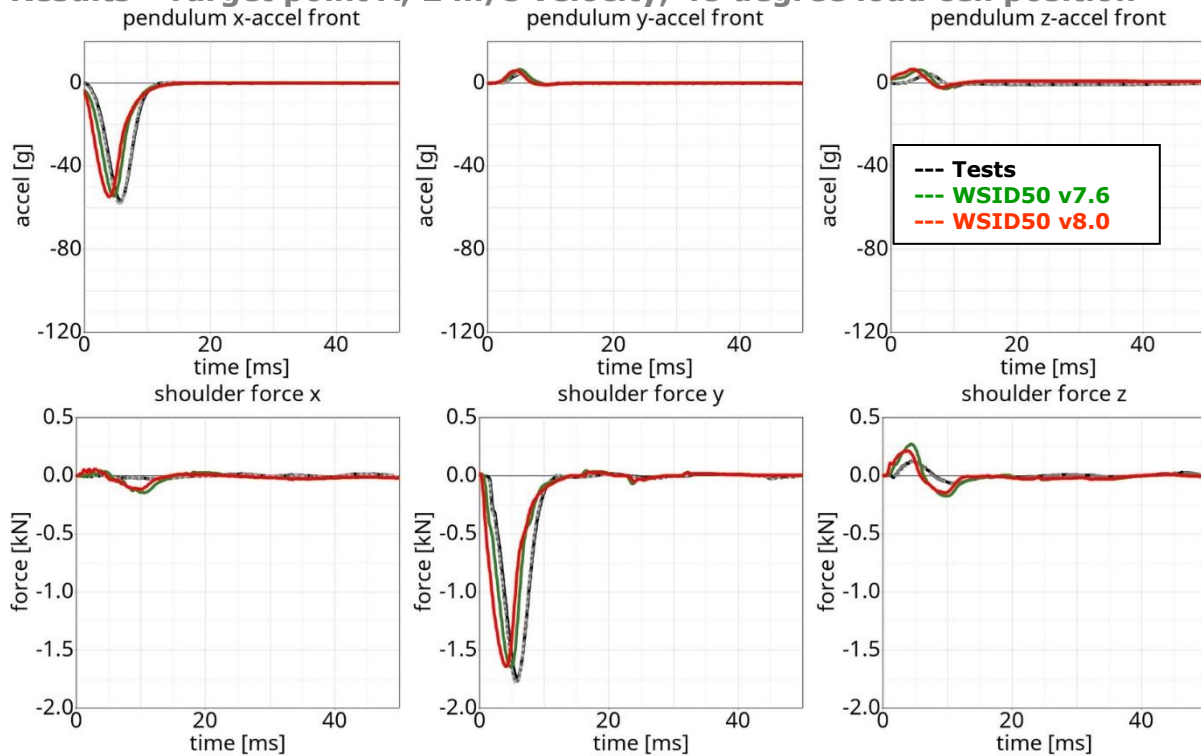


Figure 47: Results - target point A, 2 m/s velocity, 48 degree load cell position

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

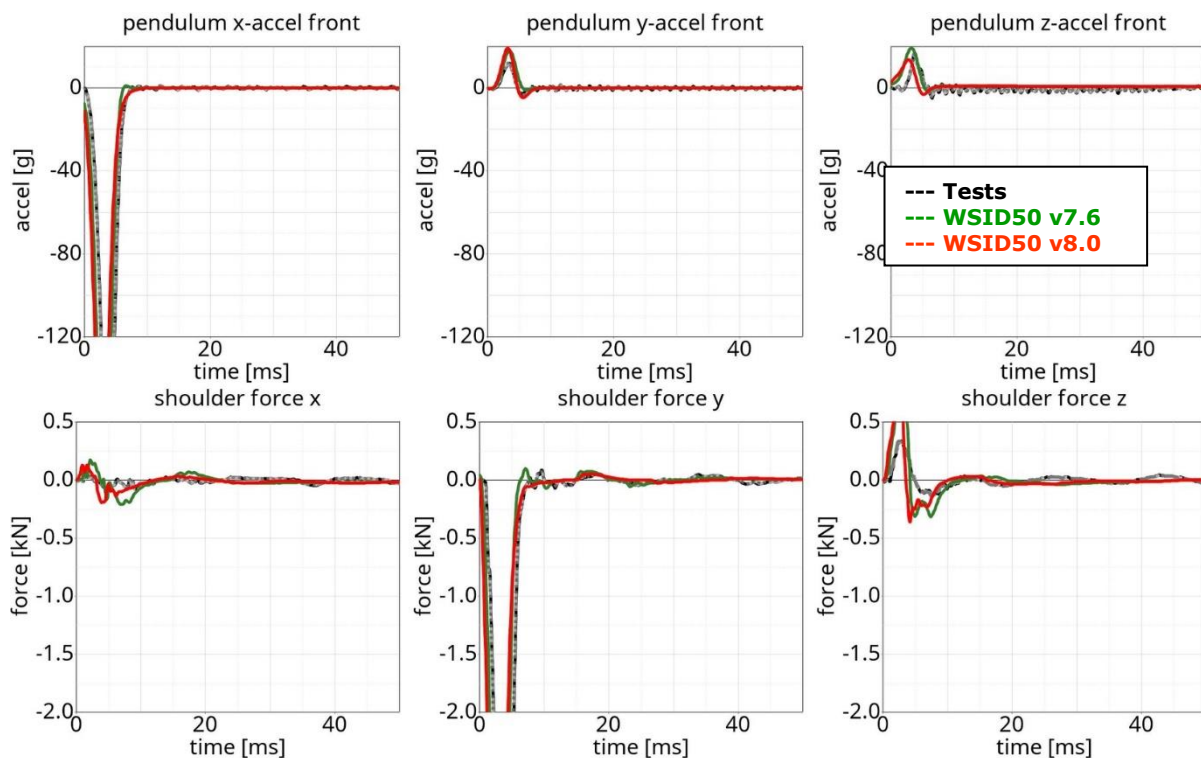


Figure 48: Results - Target point A, 4 m/s velocity, 48 degree load cell position

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

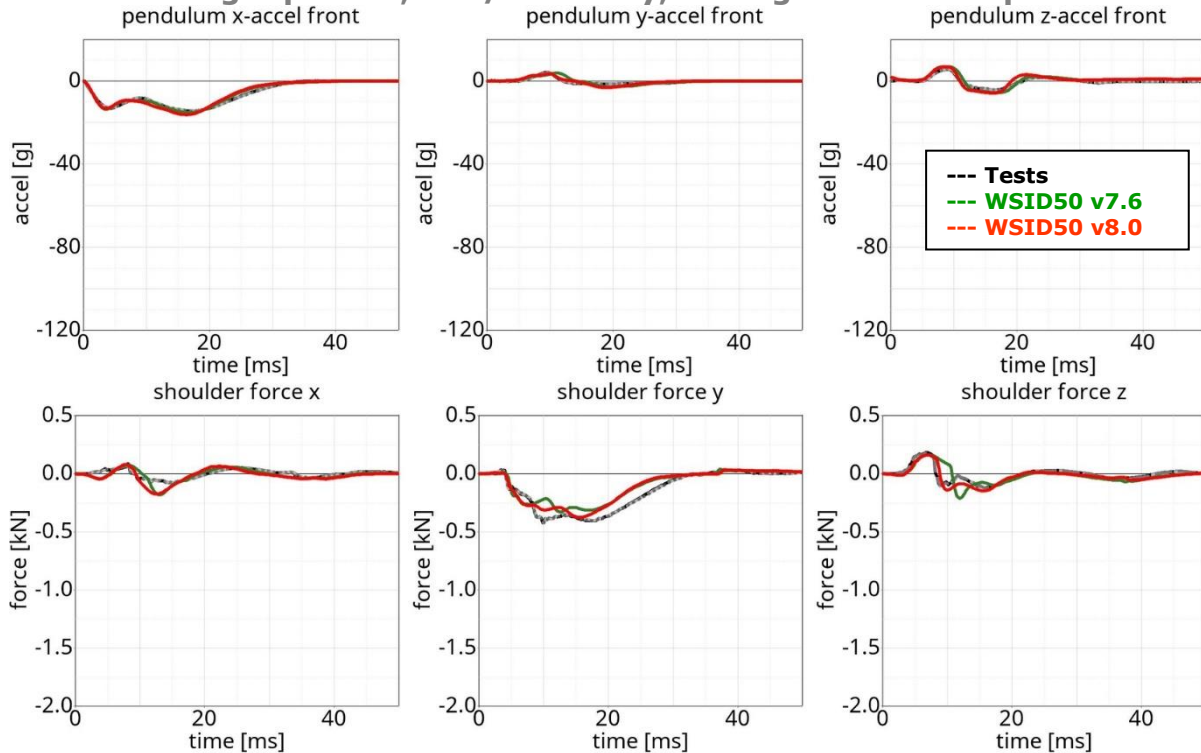


Figure 49: Results - Target point B, 2 m/s velocity, 48 degree load cell position

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

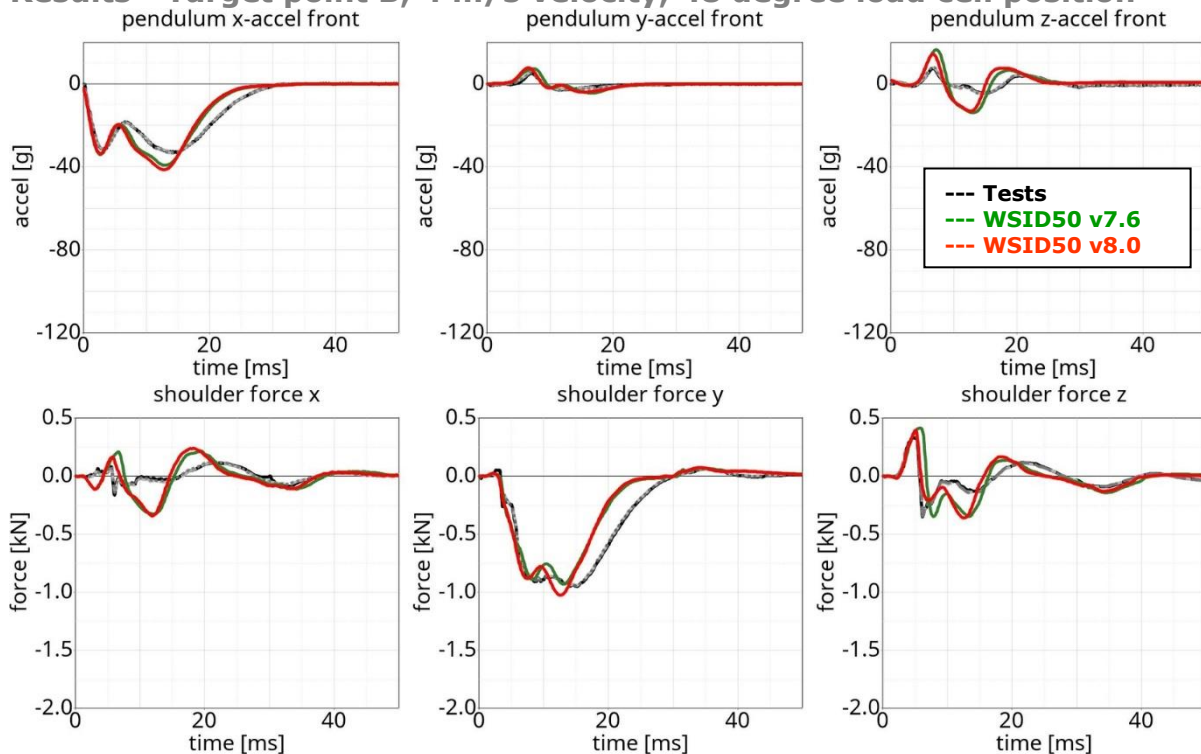


Figure 50: Results - Target point B, 4 m/s velocity, 48 degree load cell position

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

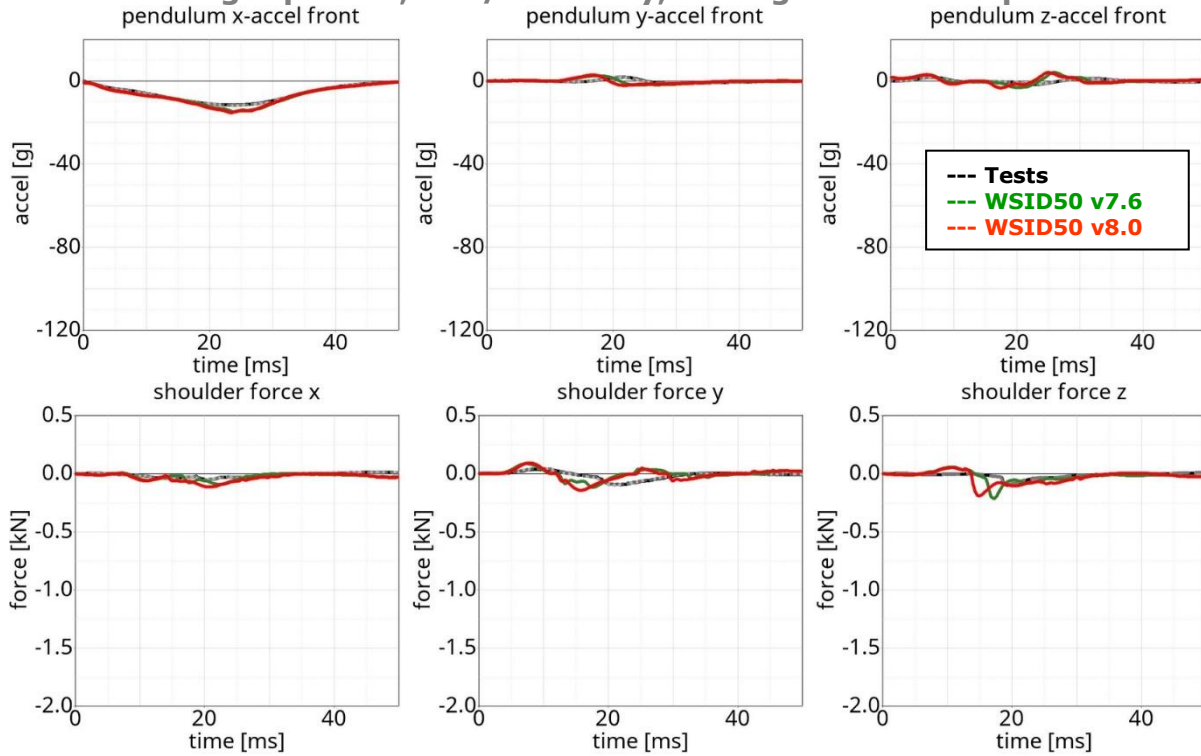


Figure 51: Results - Target point C, 2 m/s velocity, 48 degree load cell position

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

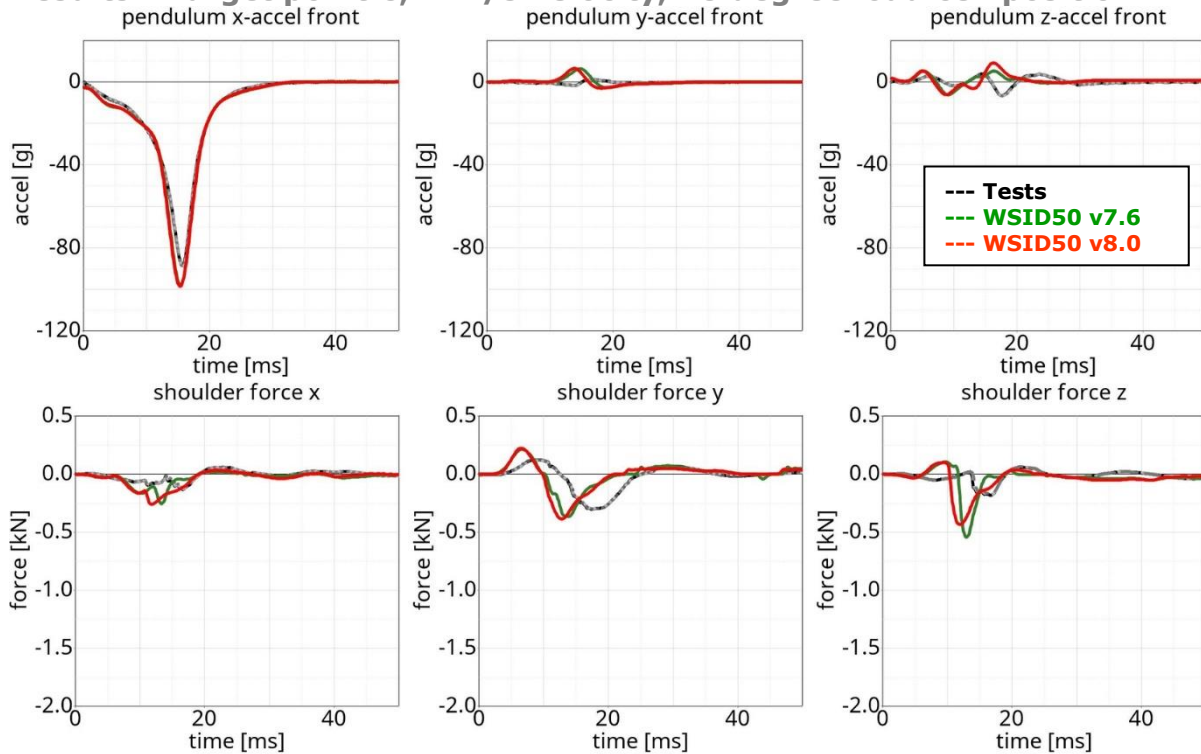


Figure 52: Results - Target point C, 4 m/s velocity, 48 degree load cell position

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

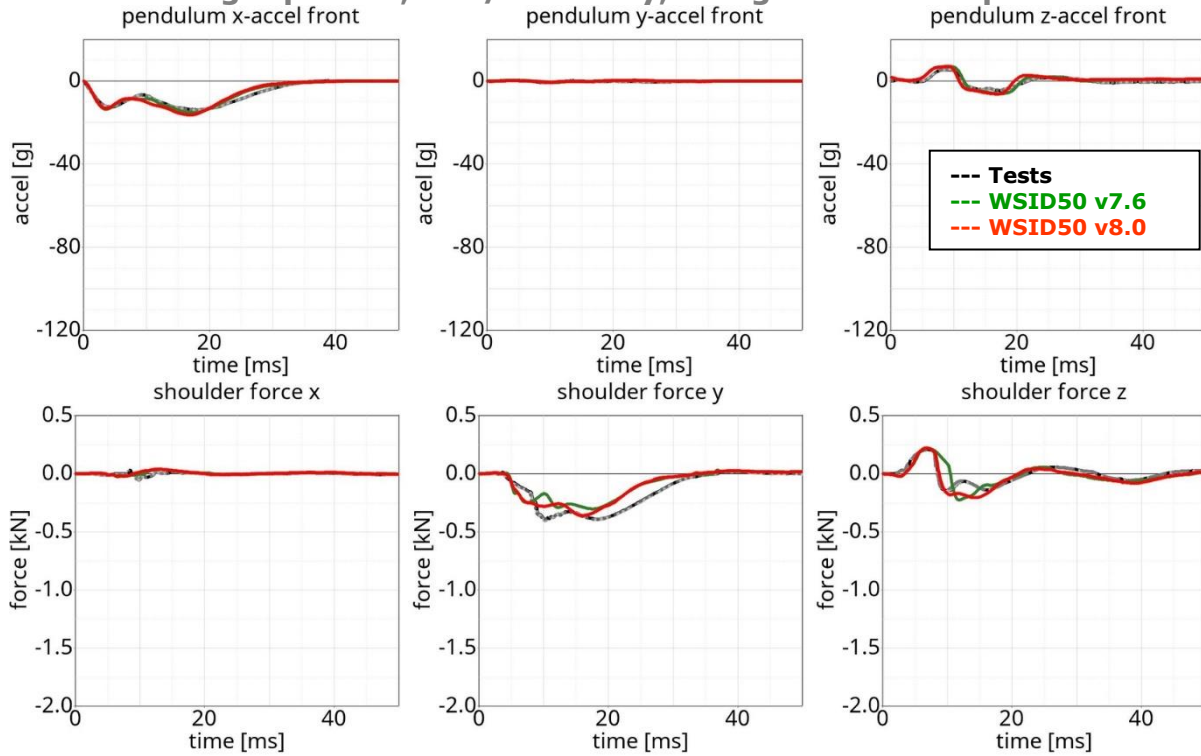


Figure 53: Results - Target point B, 2 m/s velocity, 8 degree load cell position

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

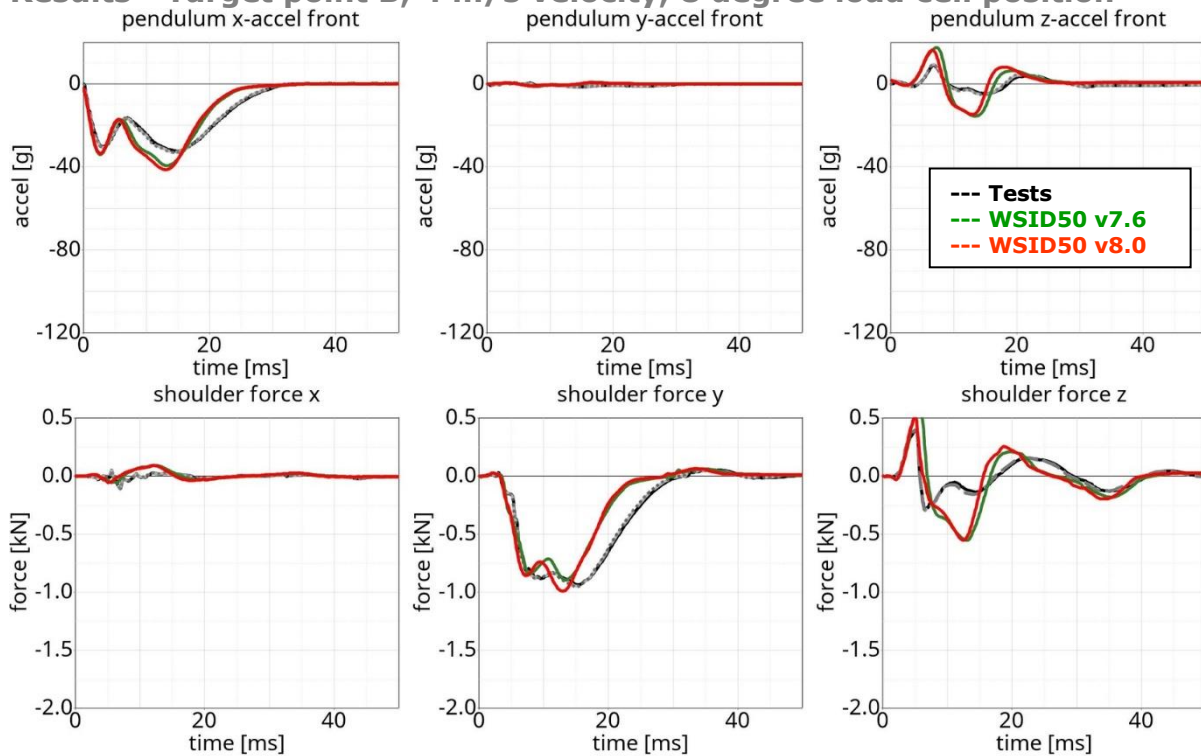


Figure 54: Results - Target point B, 4 m/s velocity, 8 degree load cell position

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

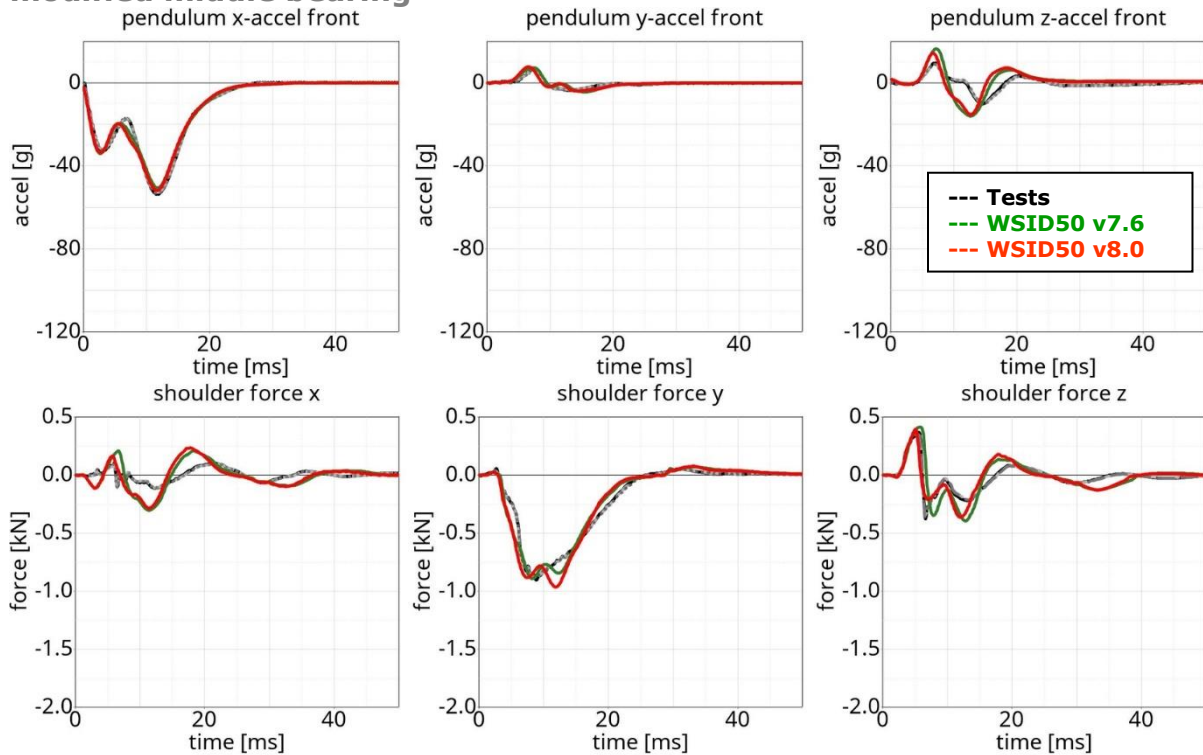


Figure 55: Results - Target point B, 4 m/s velocity, 48 degree load cell position, modified middle bearing

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

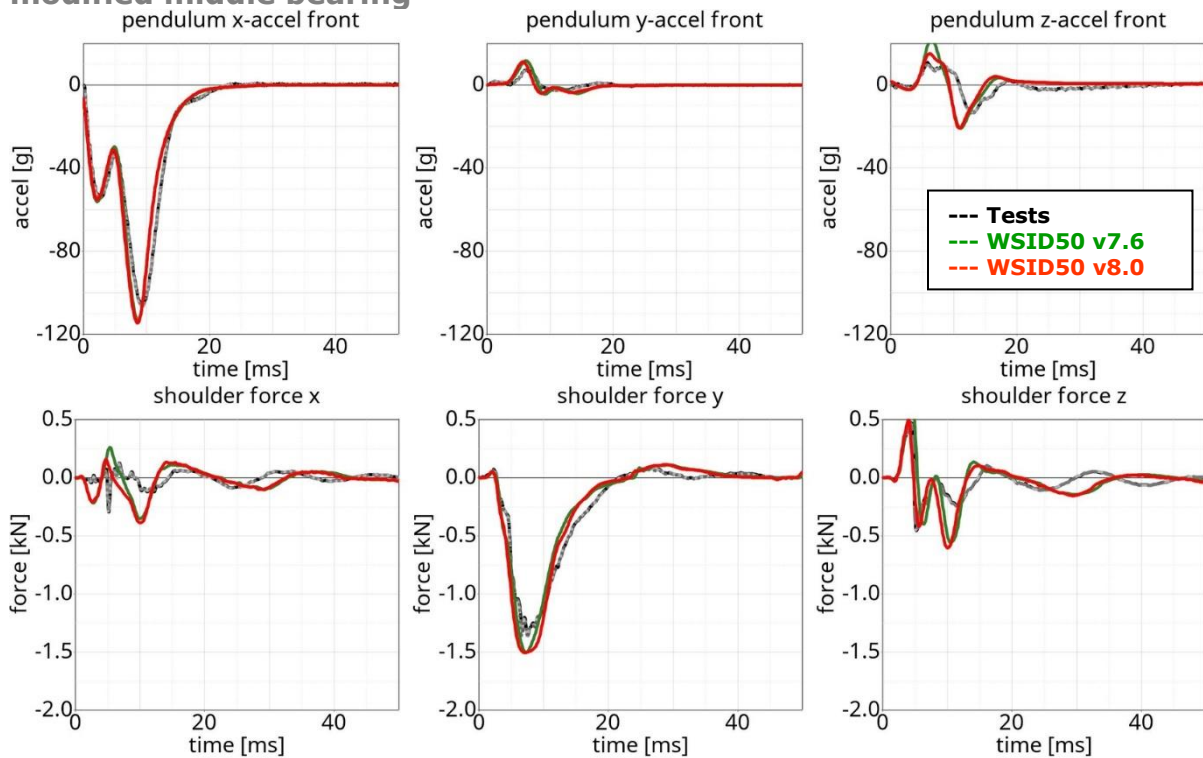


Figure 56: Results - Target point B, 6 m/s velocity, 48 degree load cell position, modified middle bearing

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.

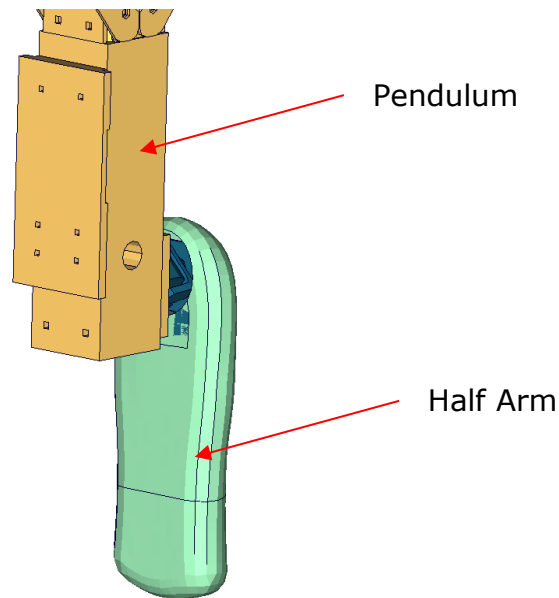


Figure 57: Arm bending test of WorldSID 50th

Results – 1g setting

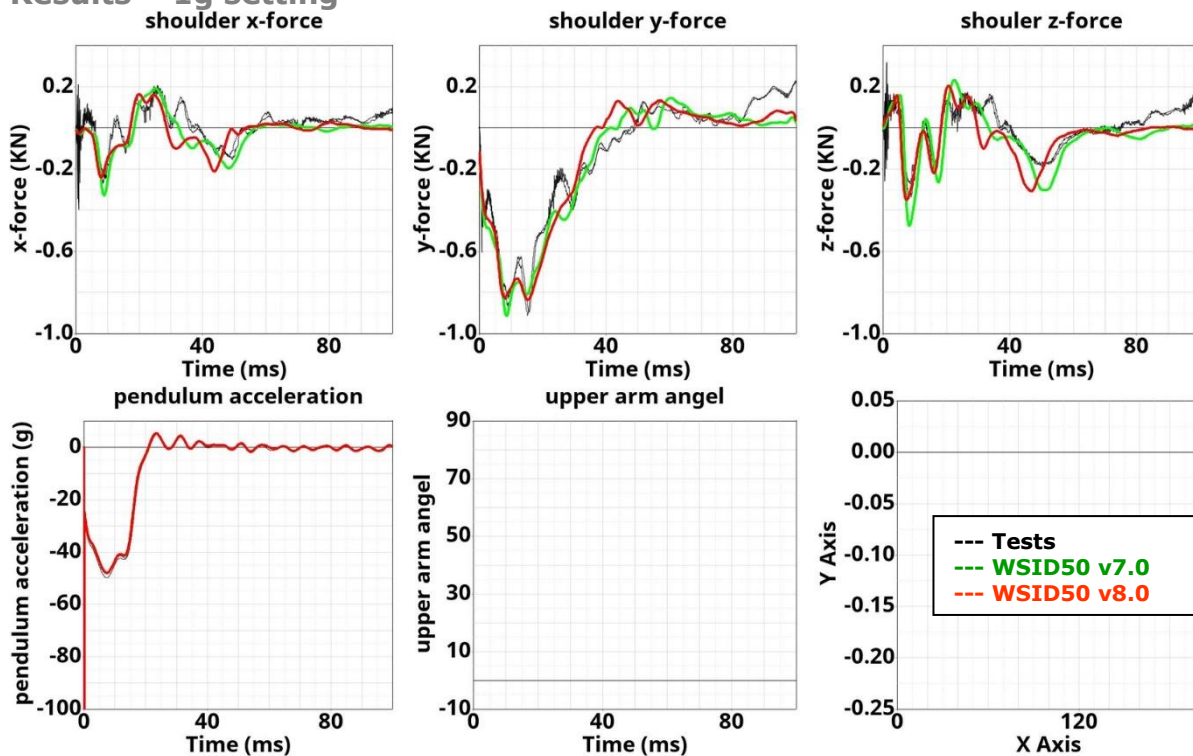


Figure 58: Results – 1g setting

Results – fixed setting

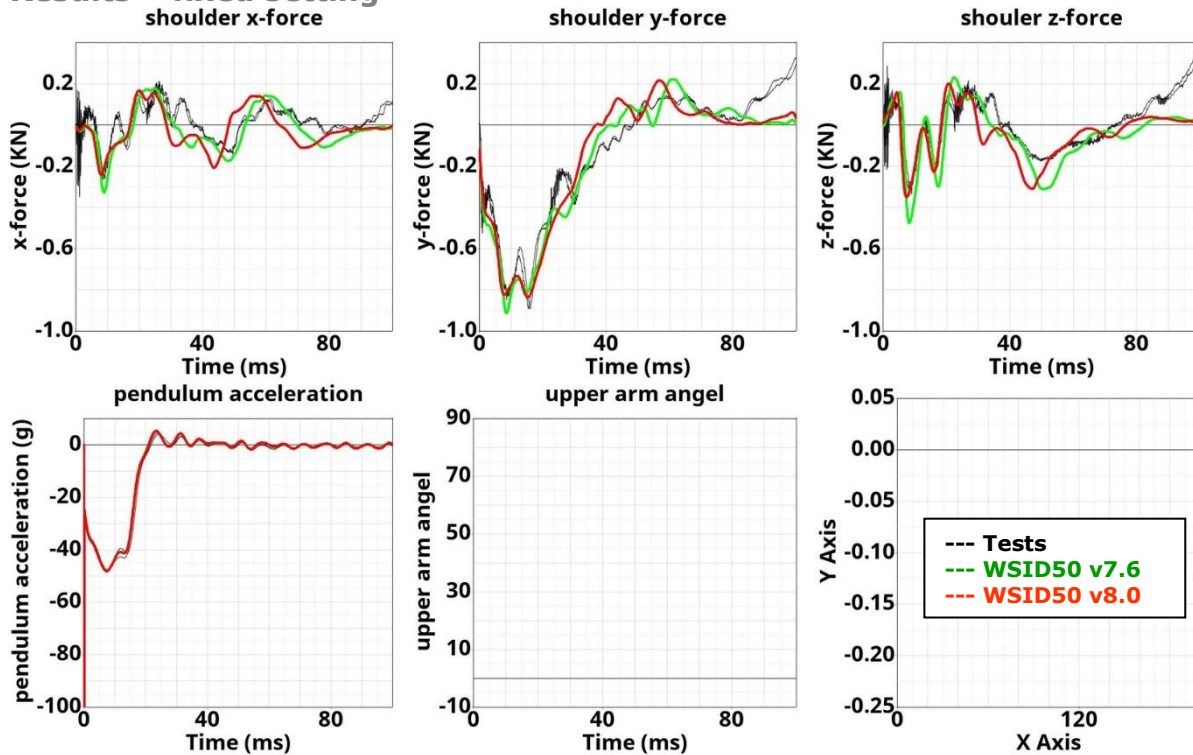


Figure 59: Results – fixed setting

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:

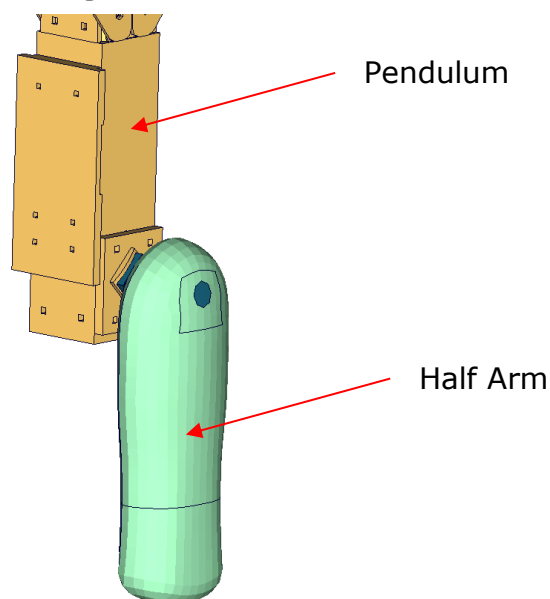


Figure 60: Arm joint test of WorldSID 50th, no additional force

Results – no additional force, low velocity

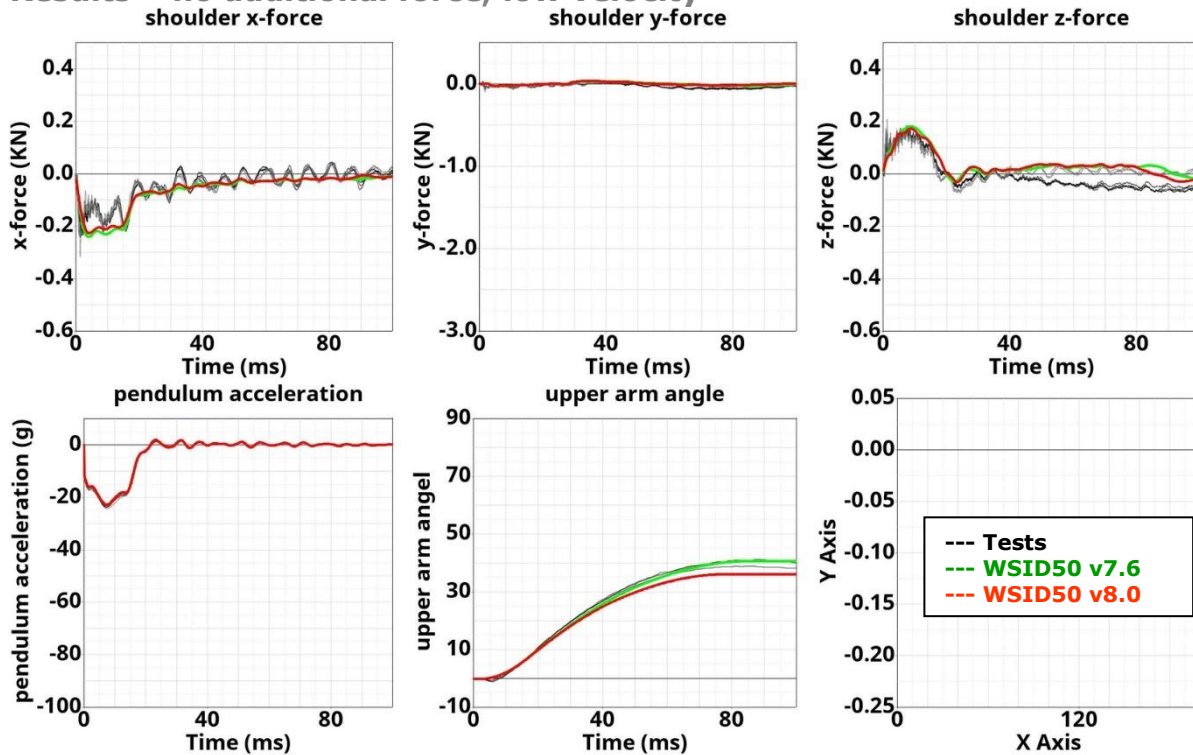


Figure 61: Results – no additional force on arm joint, low velocity

Additional force on arm joint:

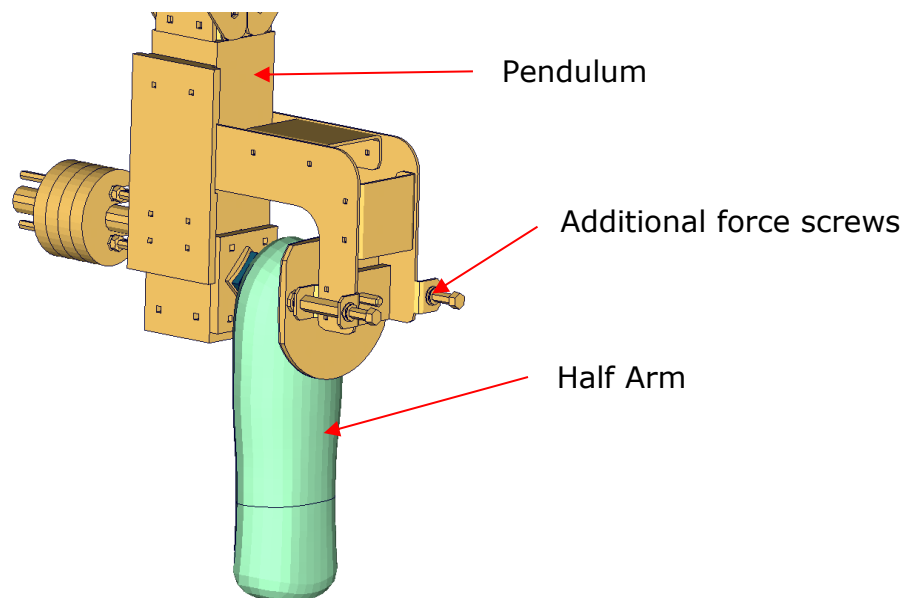


Figure 62: Arm joint test of WorldSID 50th, no additional force

Results – low additional force, high velocity

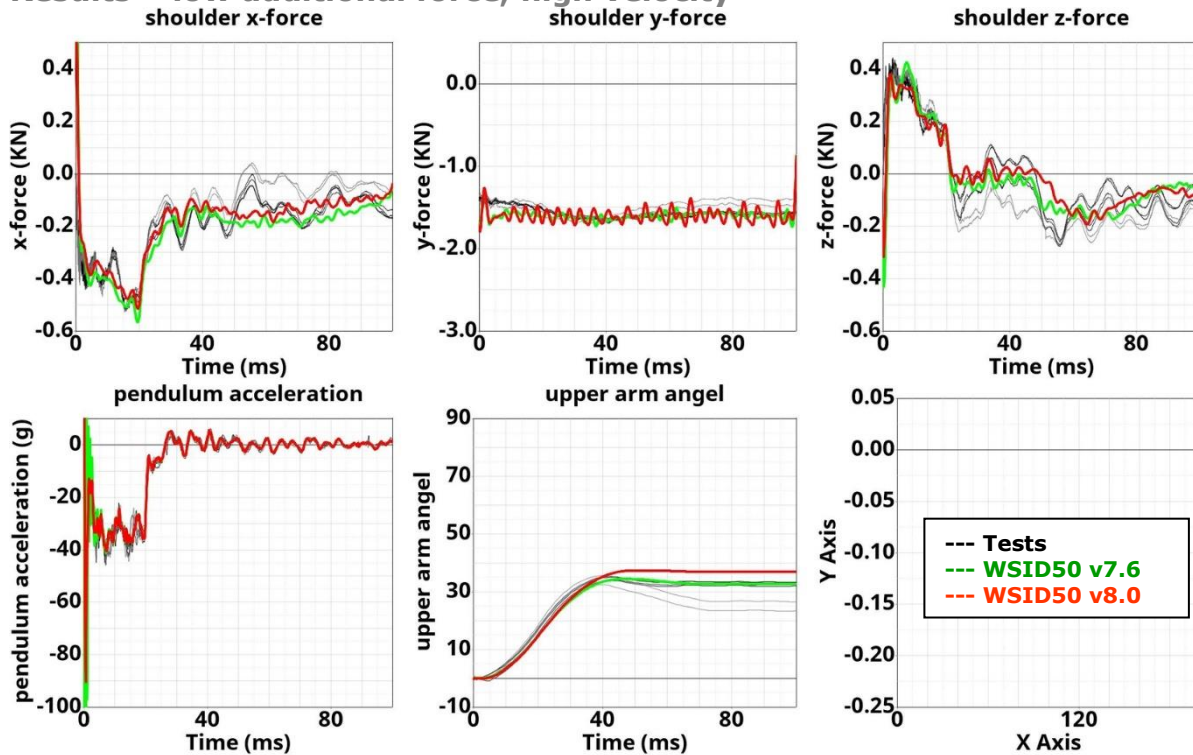


Figure 63: Results – low additional force on arm joint, high velocity

Results – medium additional force, low velocity

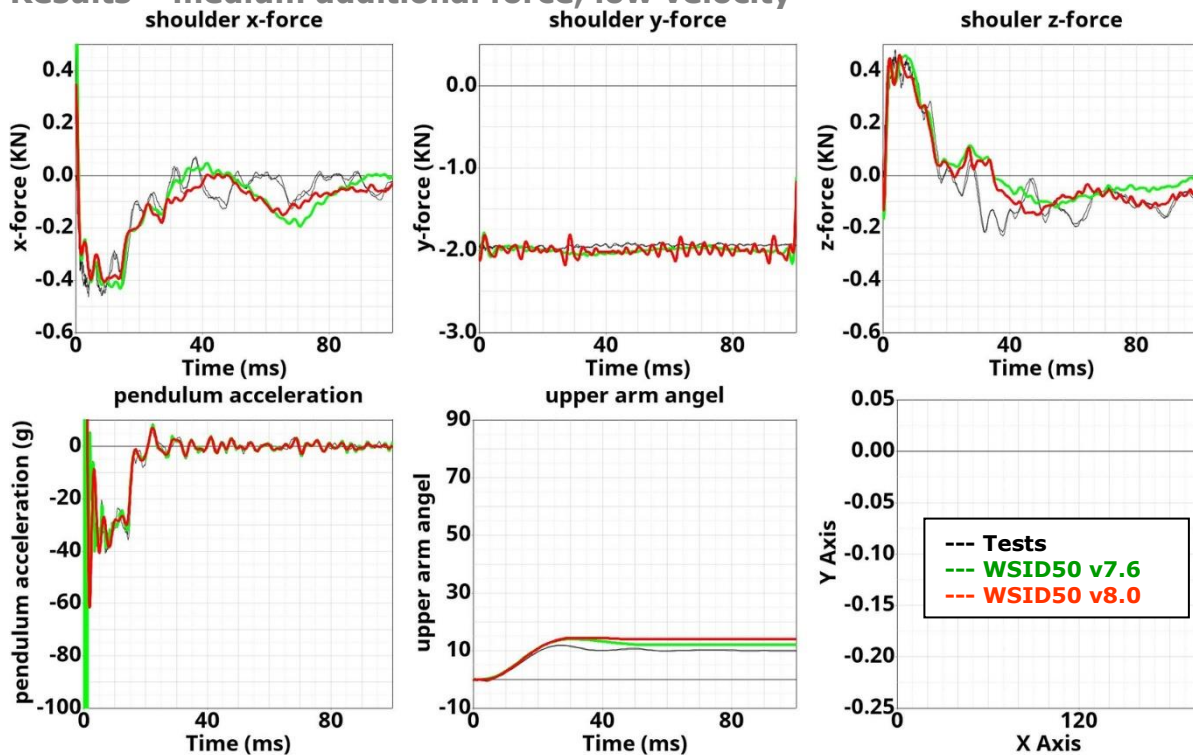


Figure 64: Results – medium additional force on arm joint, low velocity

Results – medium additional force, high velocity

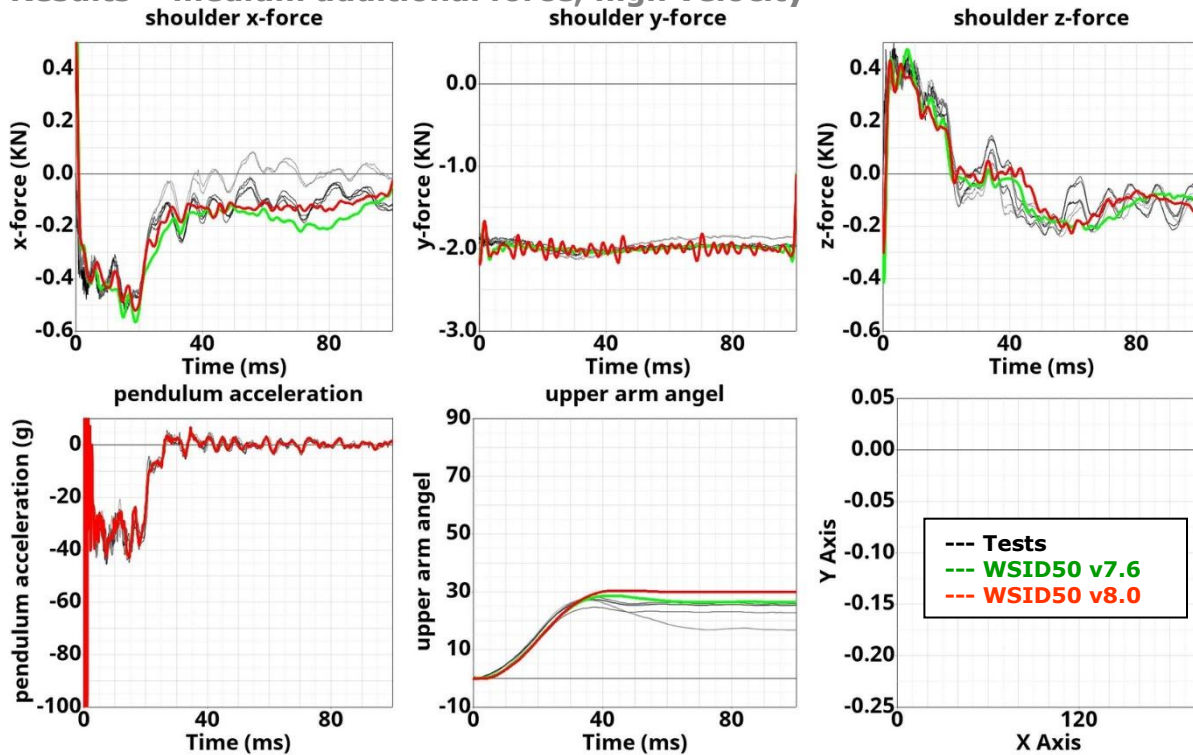


Figure 65: Results – medium additional force on arm joint, high velocity

Results – high additional force, high velocity

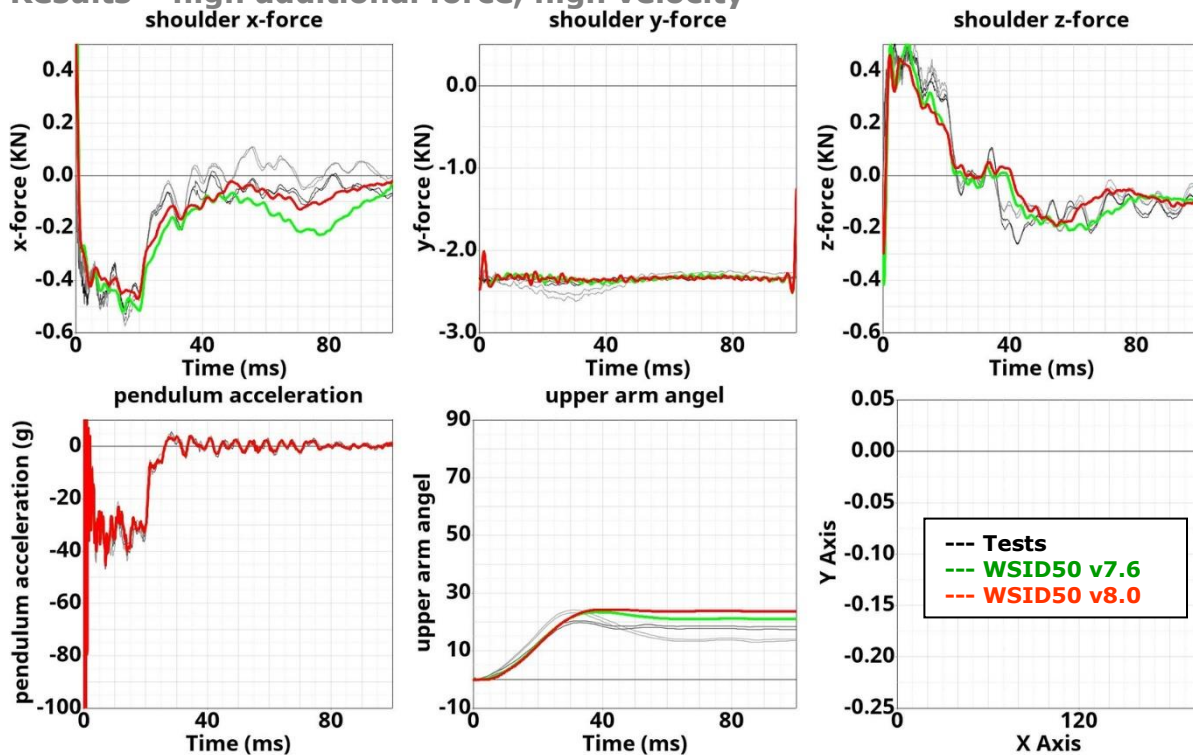


Figure 66: Results – high additional force on arm joint, high velocity

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:

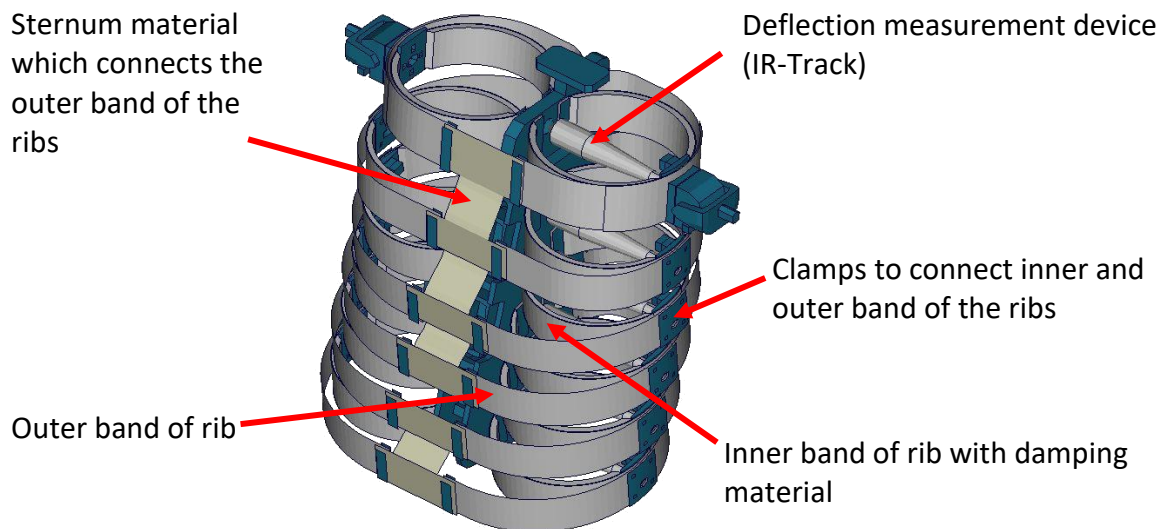


Figure 67: Thorax construction of WorldSID

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:

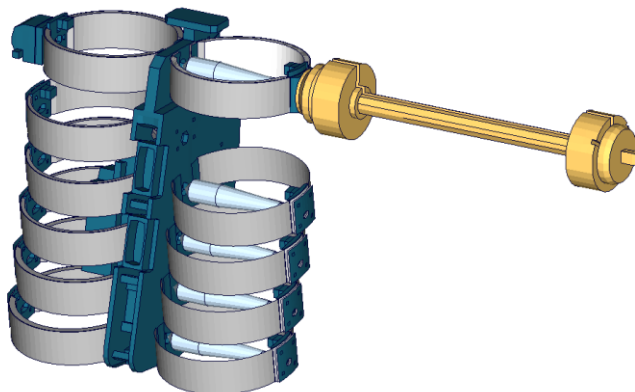


Figure 68: Shoulder rib test on inner band with damping material

Shoulder rib inner band with damping material, low velocity

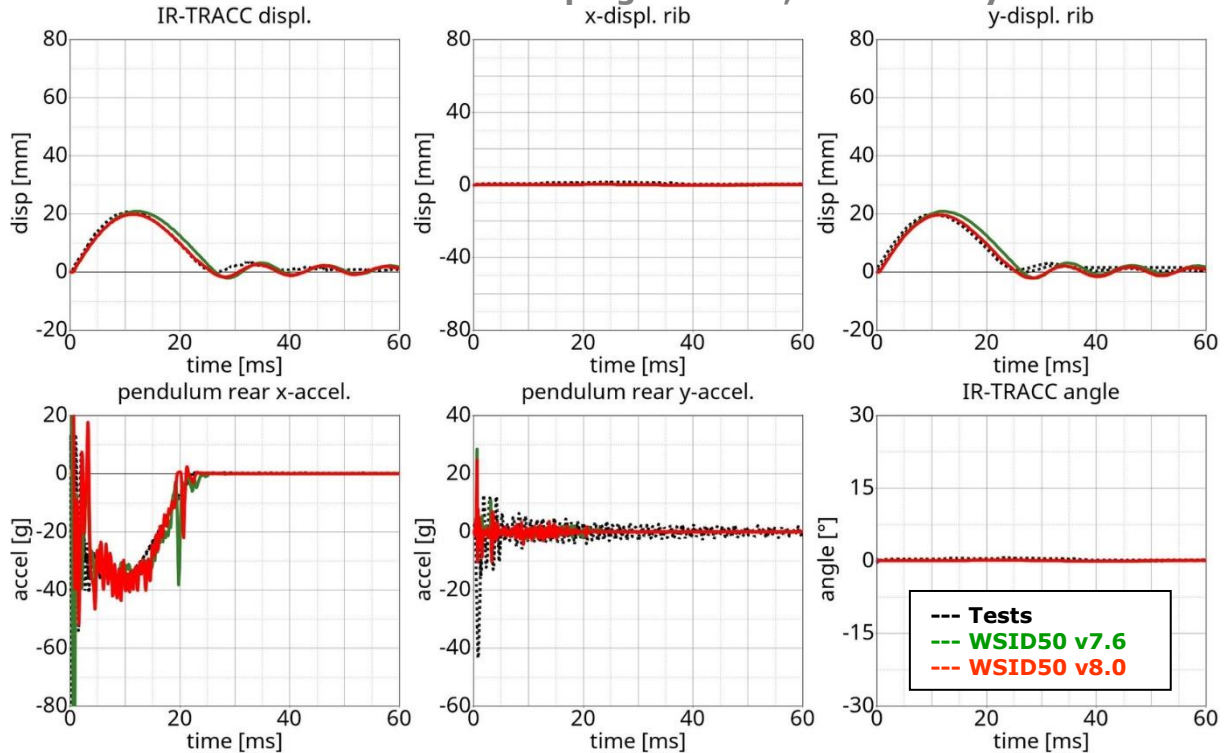


Figure 69: Shoulder rib test on inner band with damping material, low velocity

Shoulder rib inner band with damping material, high velocity

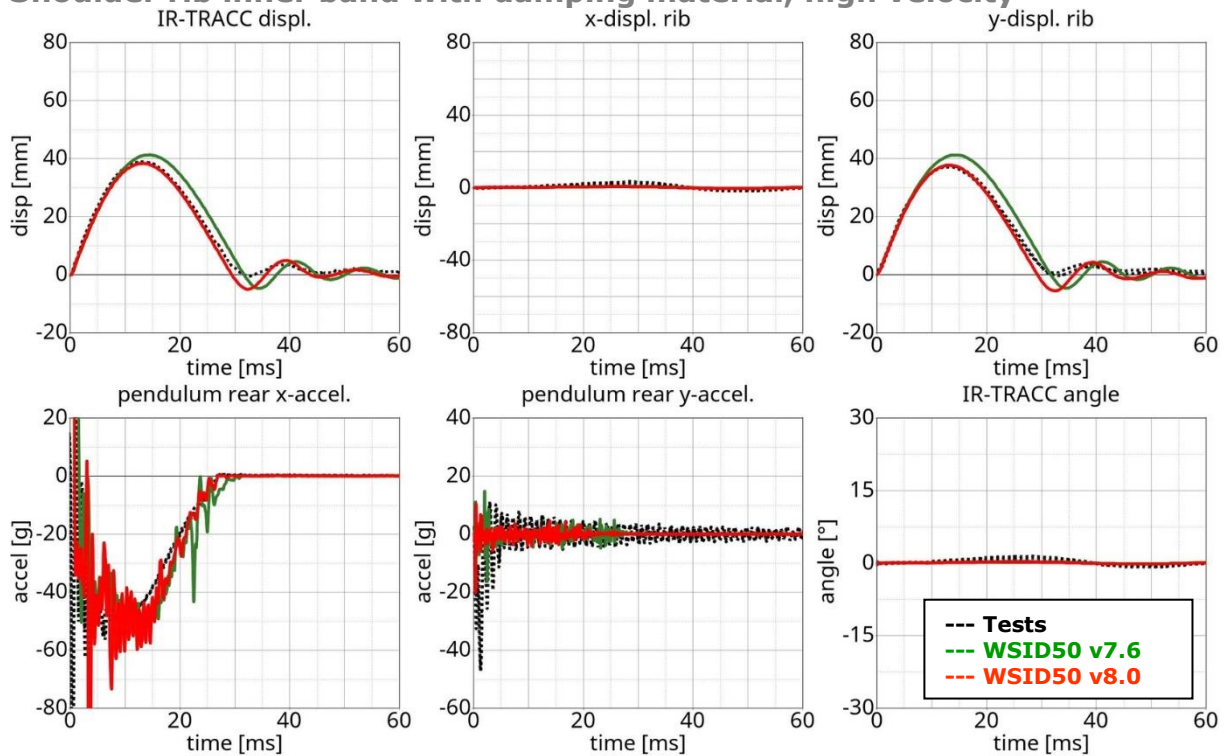


Figure 70: Shoulder rib test on inner band with damping material, high velocity

Third thorax rib:

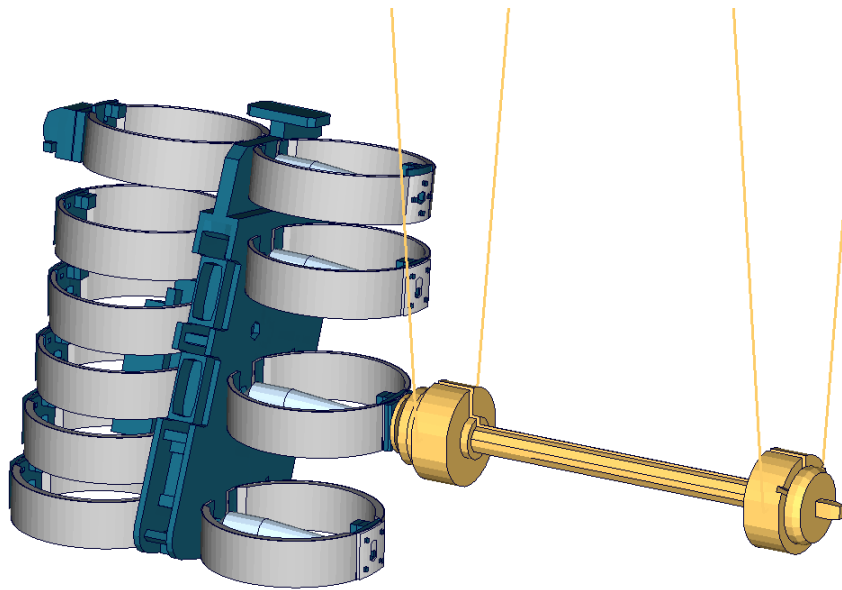


Figure 71: Third thorax rib test on inner band with damping material

Third thorax rib inner band with damping material, low velocity

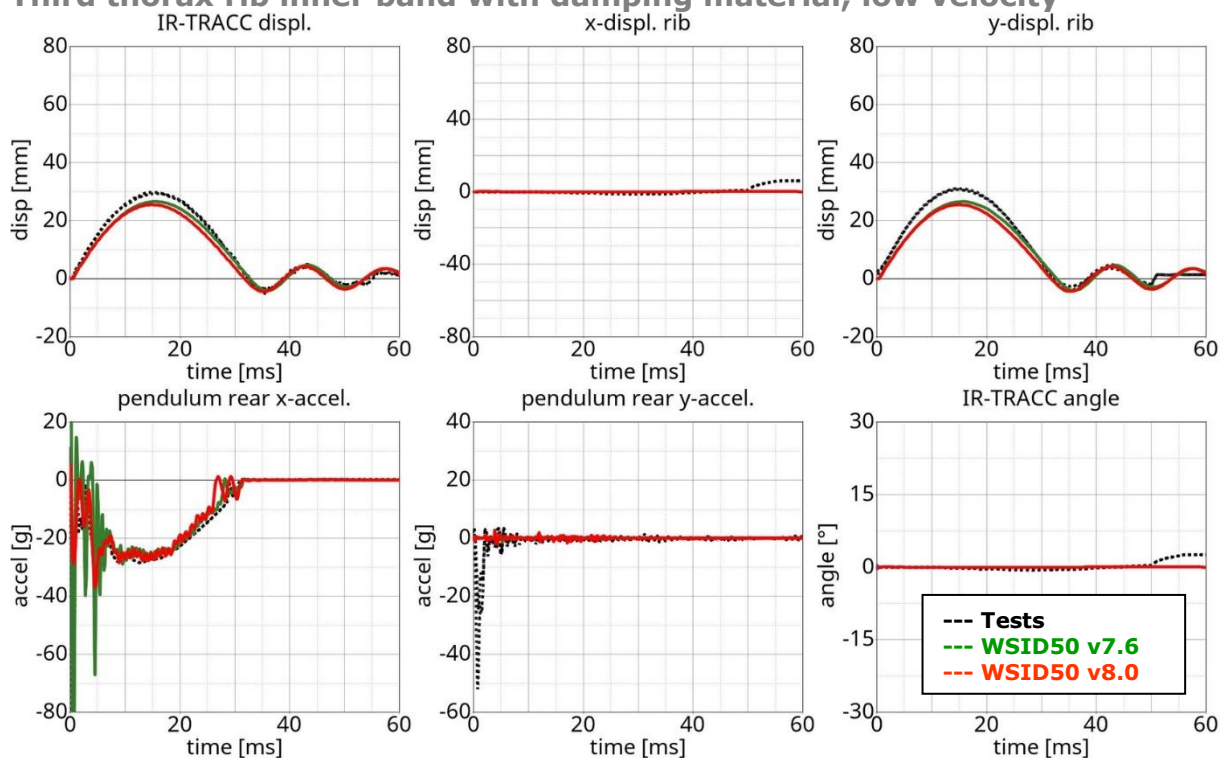


Figure 72: Shoulder rib test on inner band with damping material, low velocity

Third thorax rib inner band with damping material, high velocity

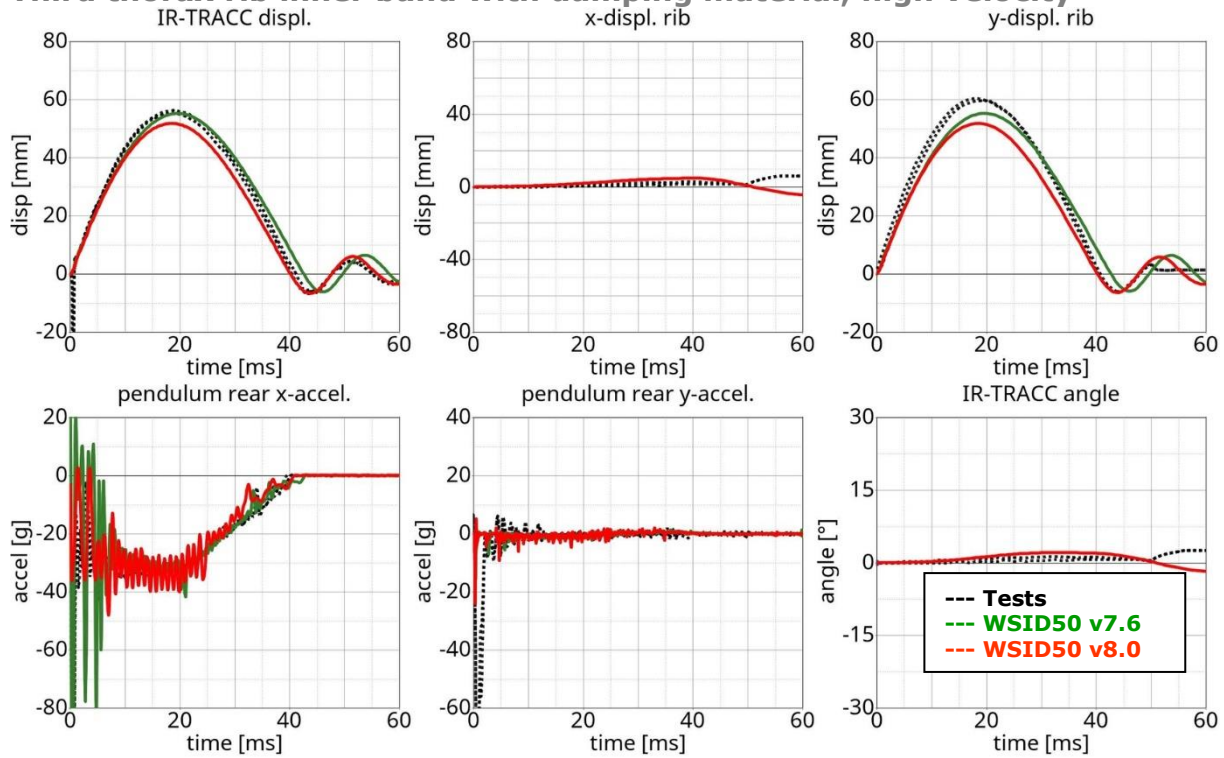


Figure 73: Shoulder rib test on inner band with damping material, high velocity

Second abdomen rib:

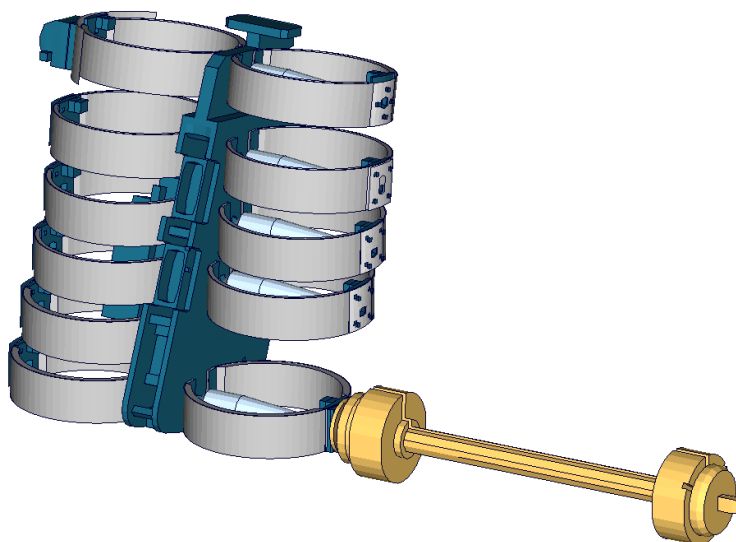


Figure 74: Second abdomen rib test on inner band with damping material.

Second abdomen rib inner band with damping material, low velocity

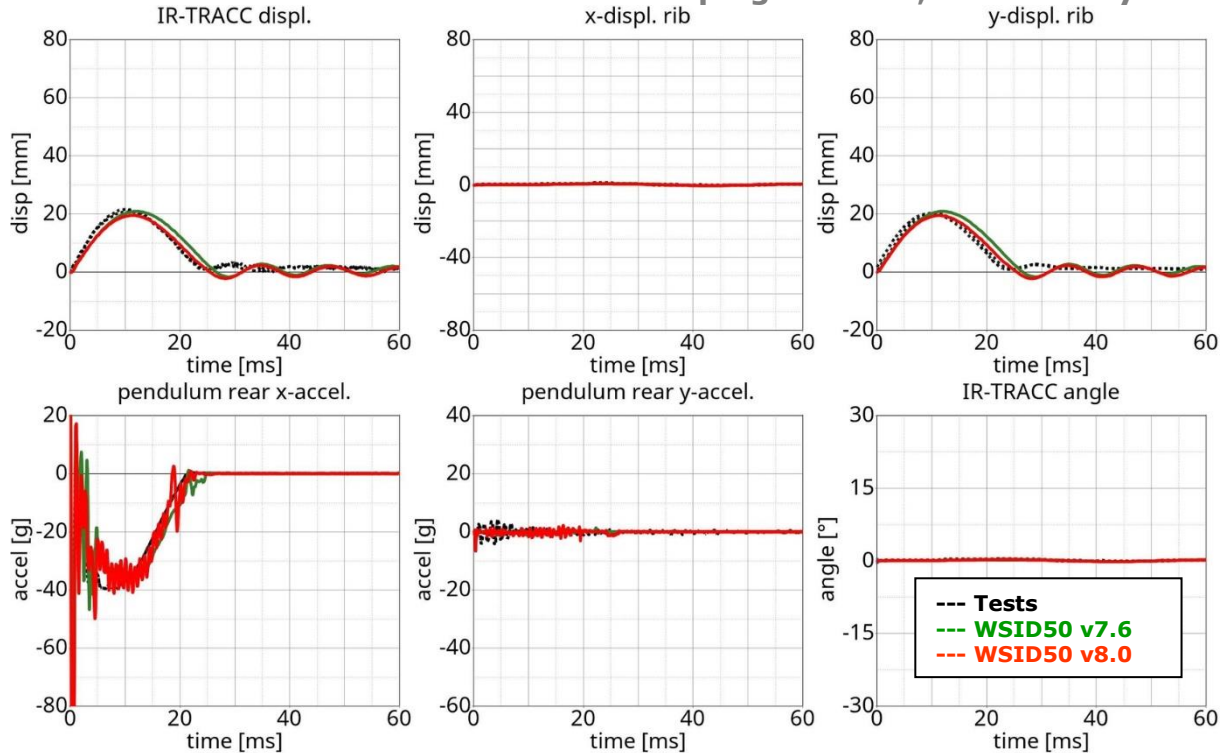


Figure 75: Second abdomen rib test on inner band with damping material, low velocity

Second abdomen rib inner band with damping material, high velocity

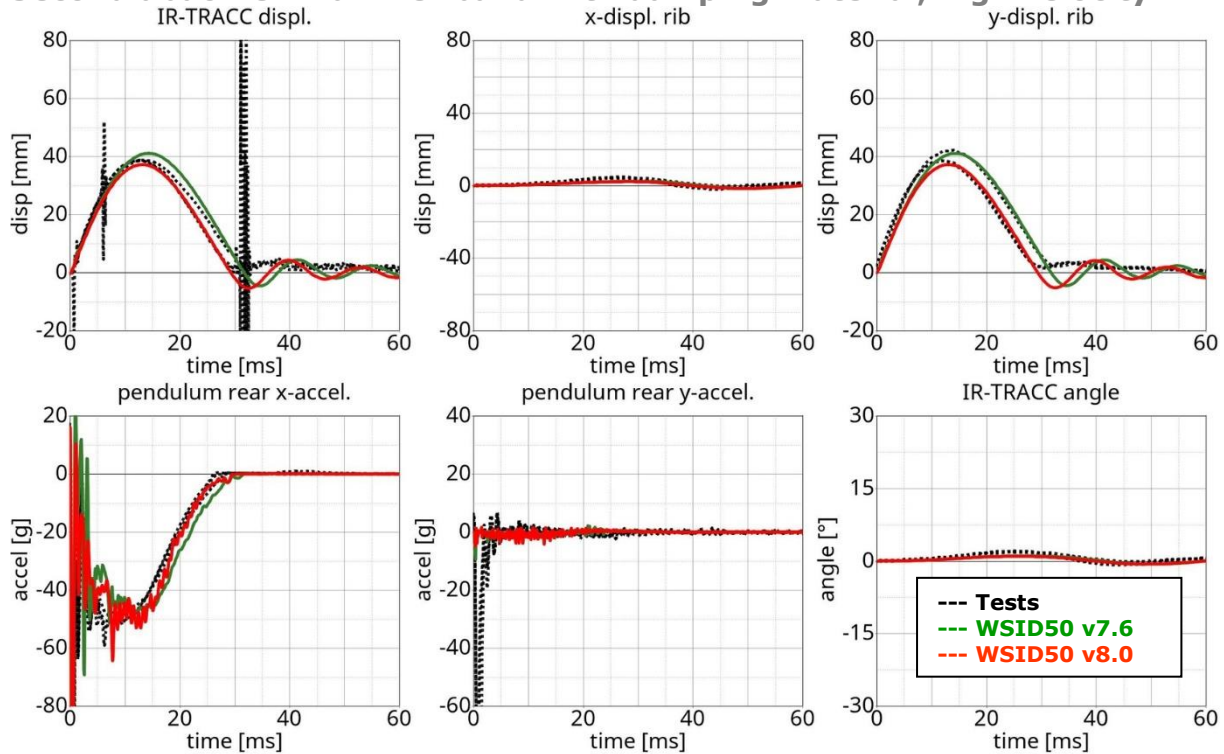


Figure 76: Second abdomen rib test on inner band with damping material, high velocity

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:

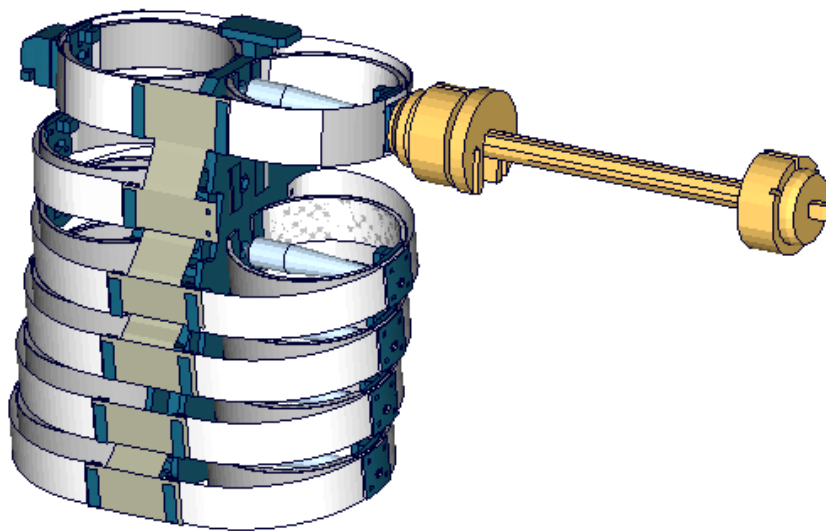


Figure 77: Shoulder rib outer band test

Shoulder rib outer band - low velocity, low mass

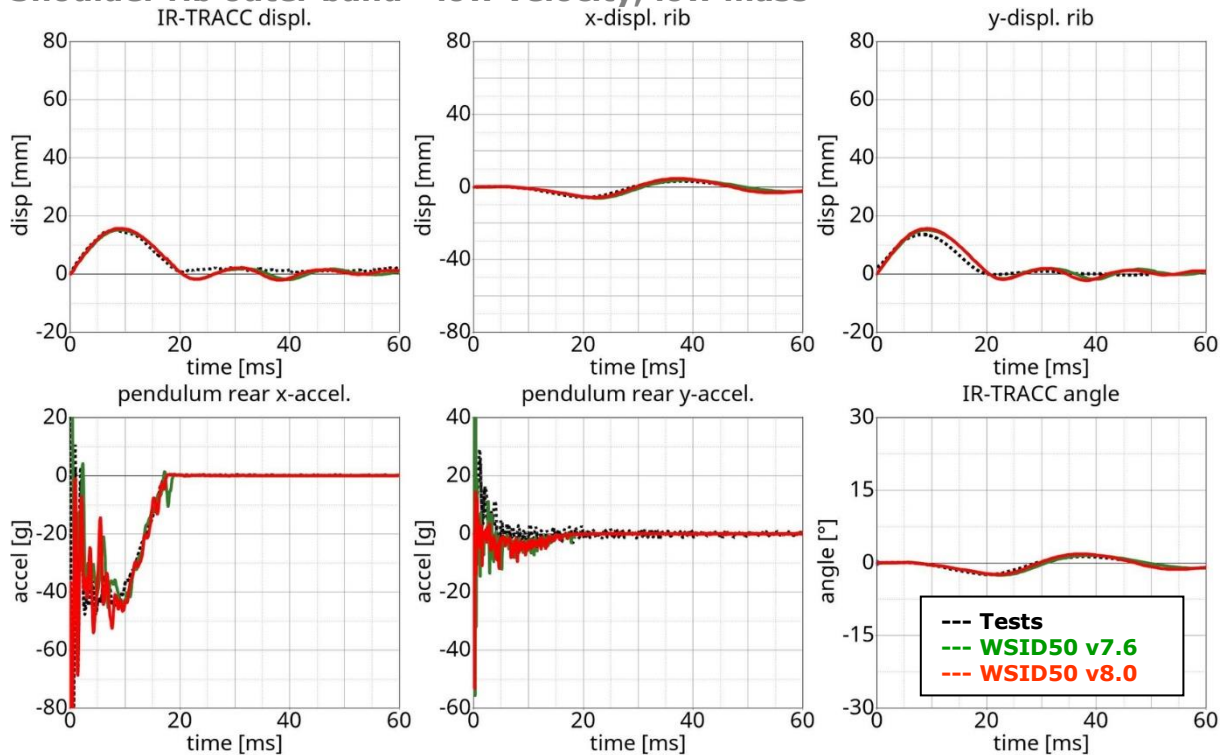


Figure 78: Shoulder rib test on outer band - low velocity and low mass

Shoulder rib outer band - low velocity, high mass

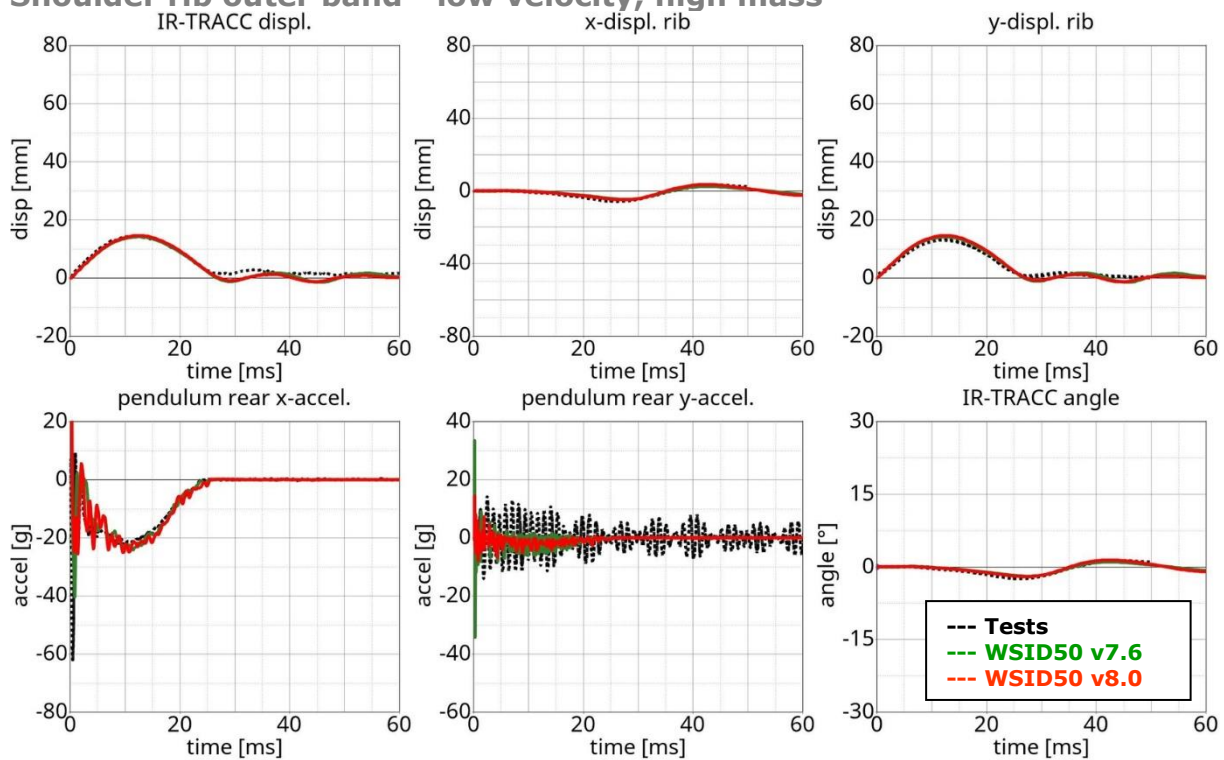


Figure 79: Shoulder rib test on outer band - low velocity and high mass

Shoulder rib outer band - medium velocity, low mass

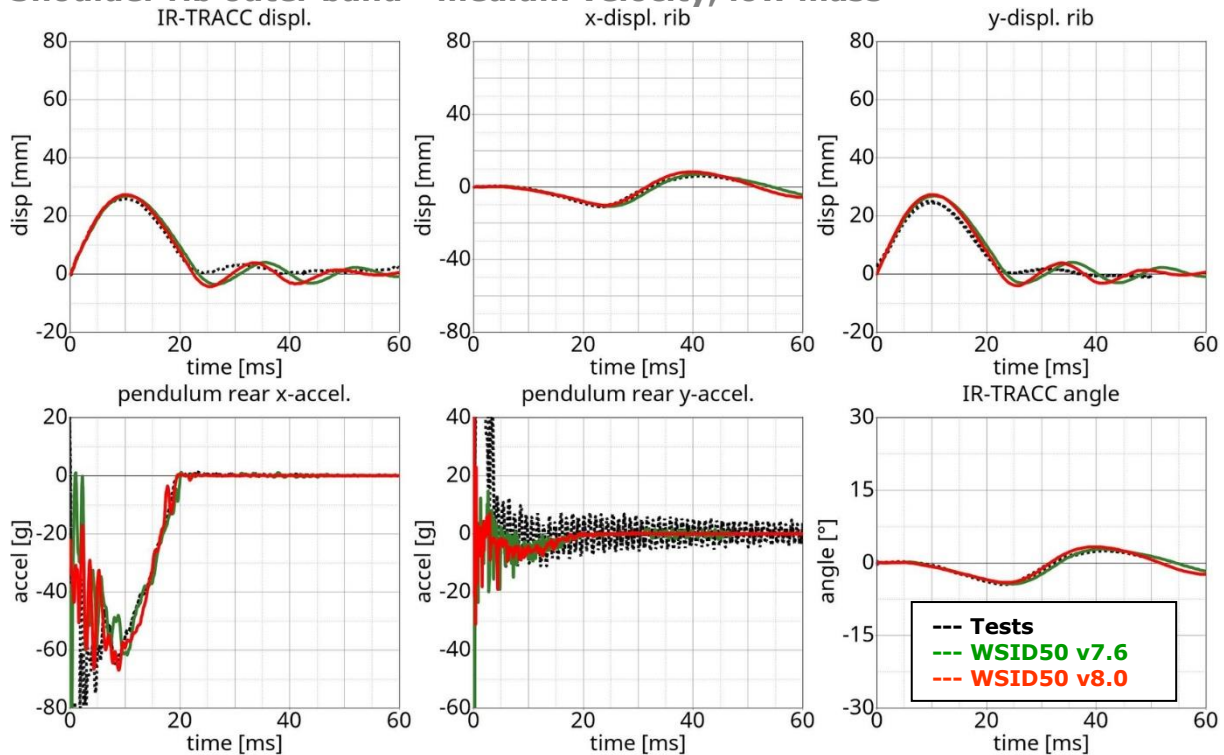


Figure 80: Shoulder rib test on outer band - middle velocity and low mass

Shoulder rib outer band - medium velocity, high mass

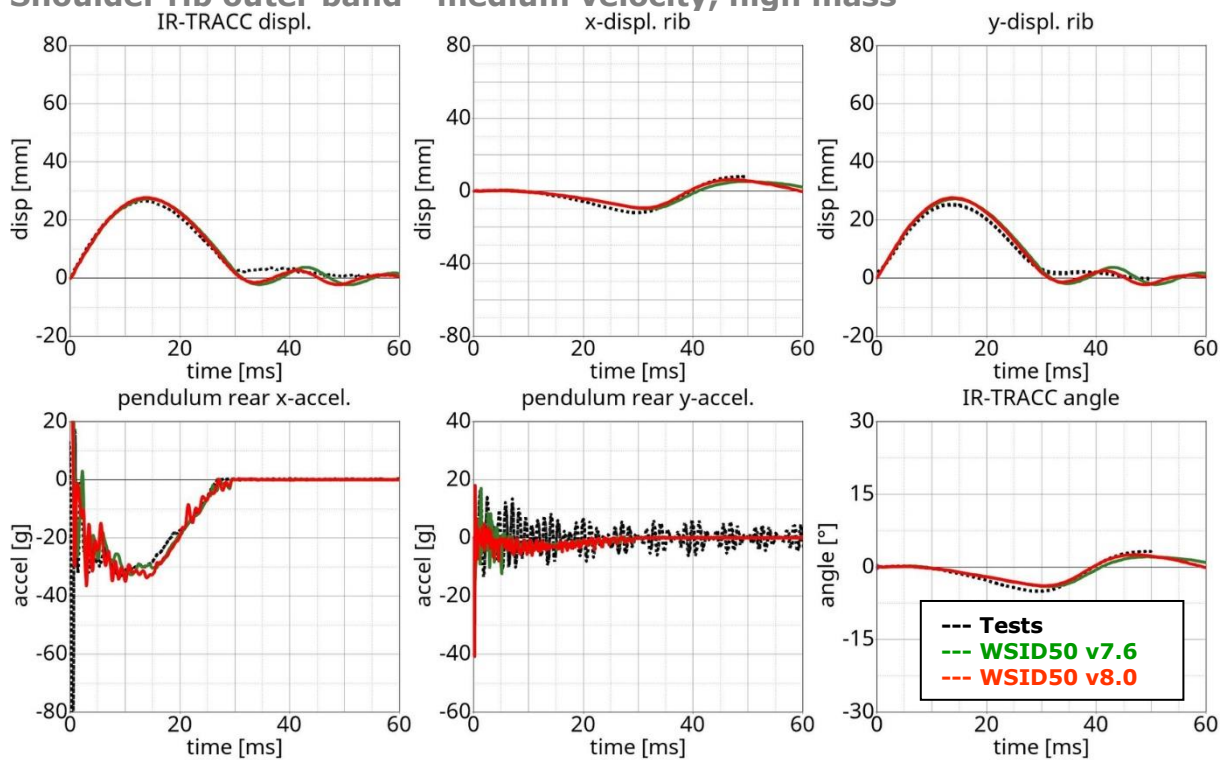


Figure 81: Shoulder rib test on outer band - middle velocity and high mass

Shoulder rib outer band - high velocity, low mass

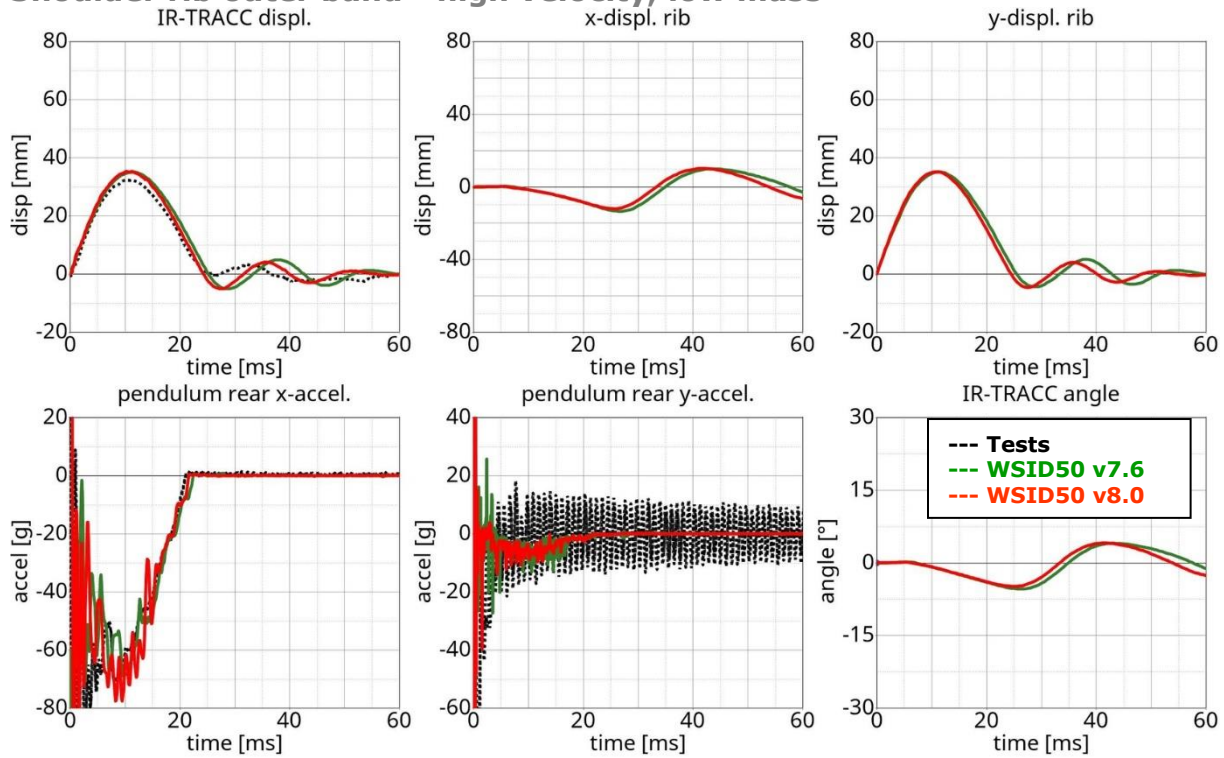


Figure 82: Shoulder rib test on outer band - high velocity and low mass

Shoulder rib outer band - high velocity, high mass

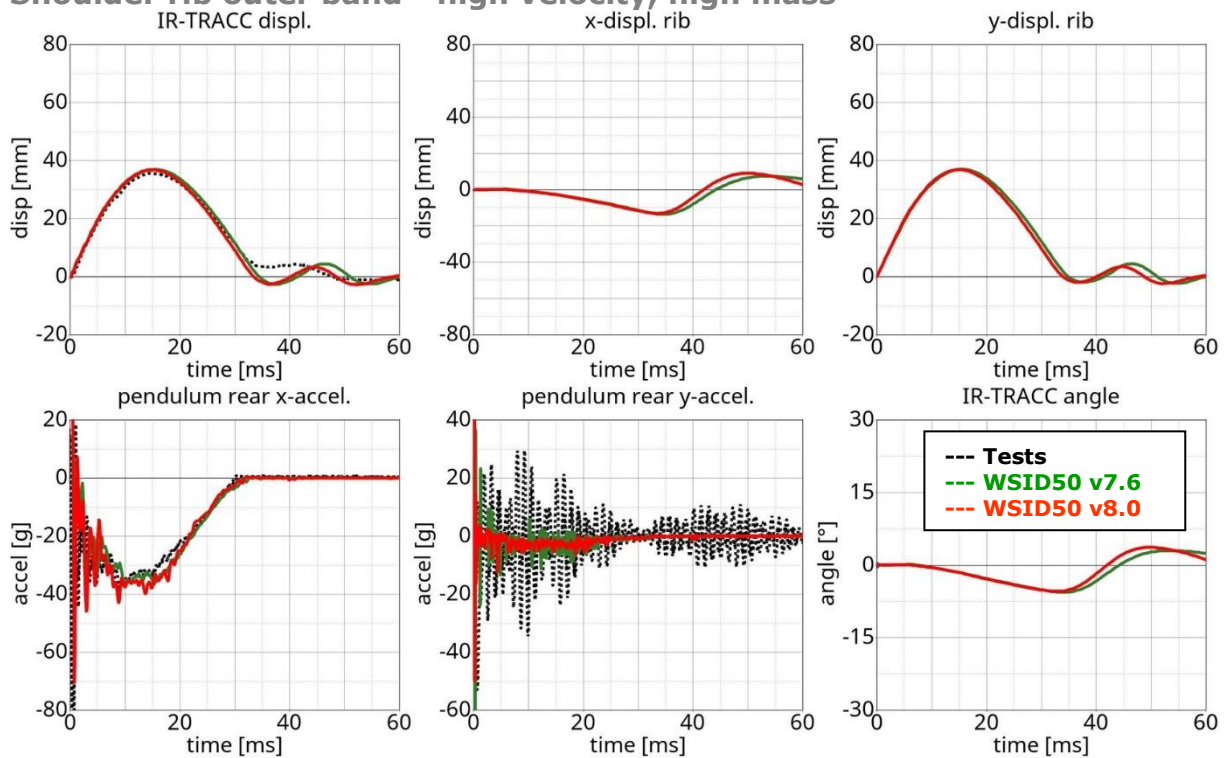


Figure 83: Shoulder rib test on outer band - high velocity and high mass

First thorax rib:

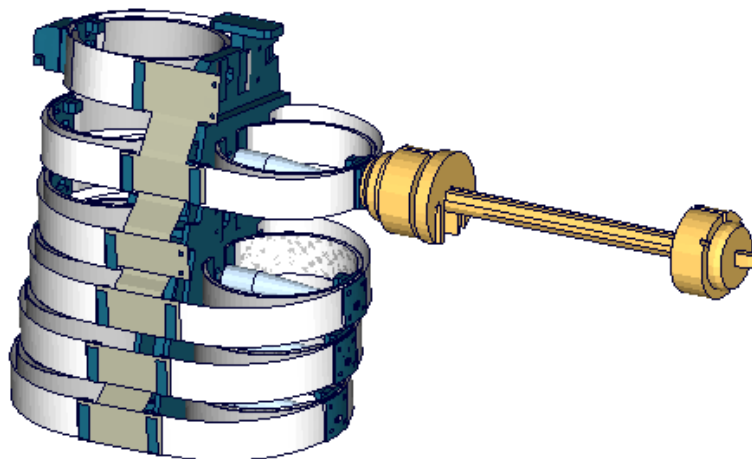


Figure 84: First thorax rib outer band test

First thorax rib outer band - low velocity, low mass

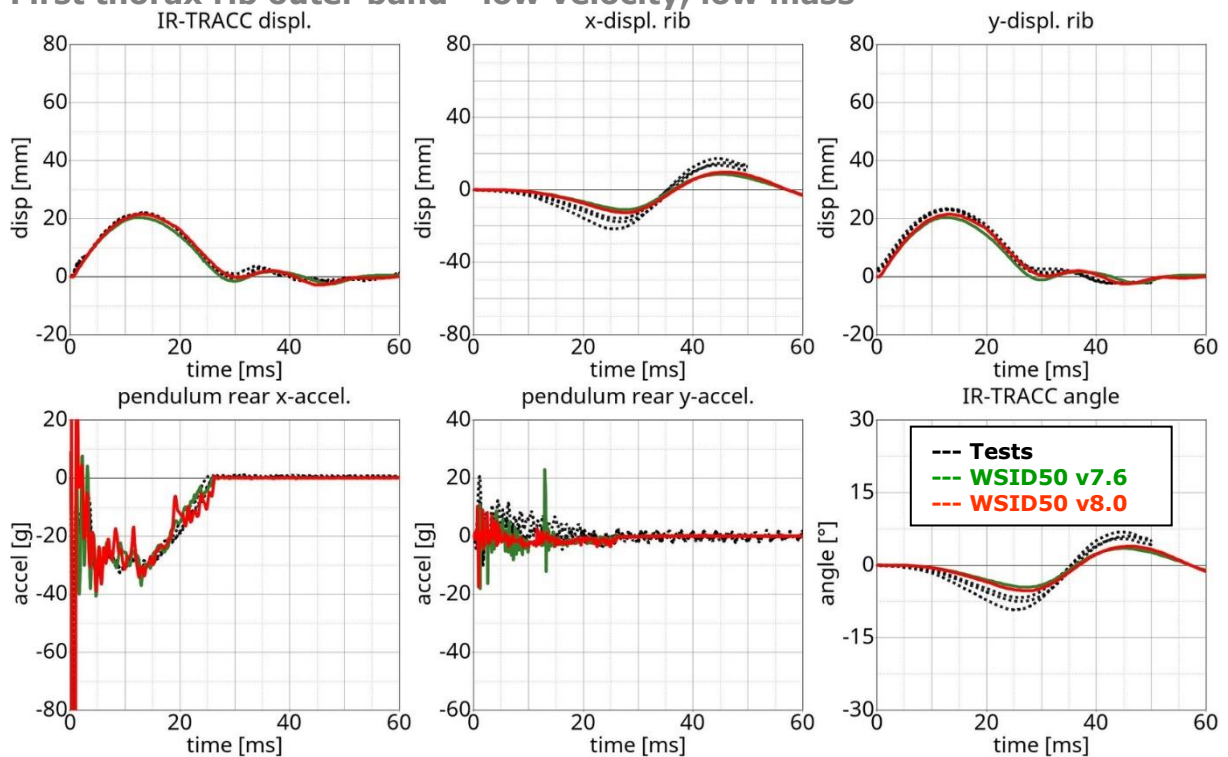


Figure 85: First thorax rib test on outer band - low velocity and low mass

First thorax rib outer band - low velocity, high mass

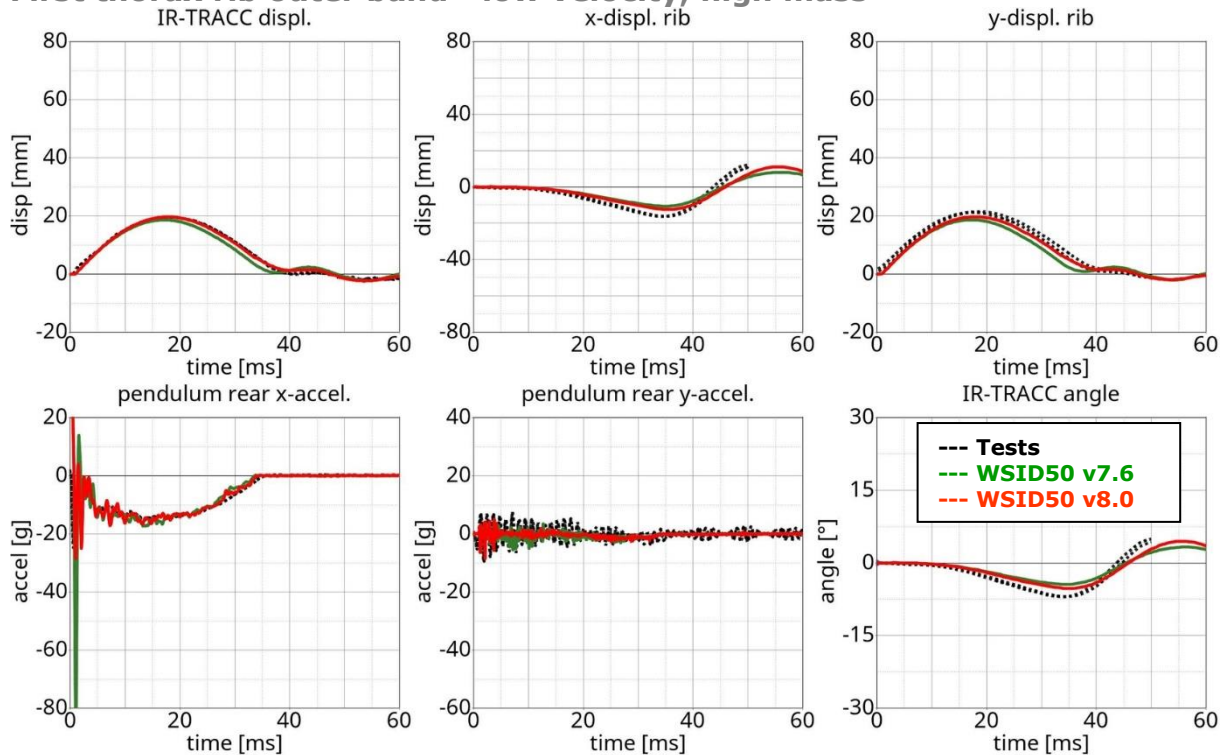


Figure 86: First thorax rib test on outer band - low velocity and high mass

First thorax rib outer band - medium velocity, low mass

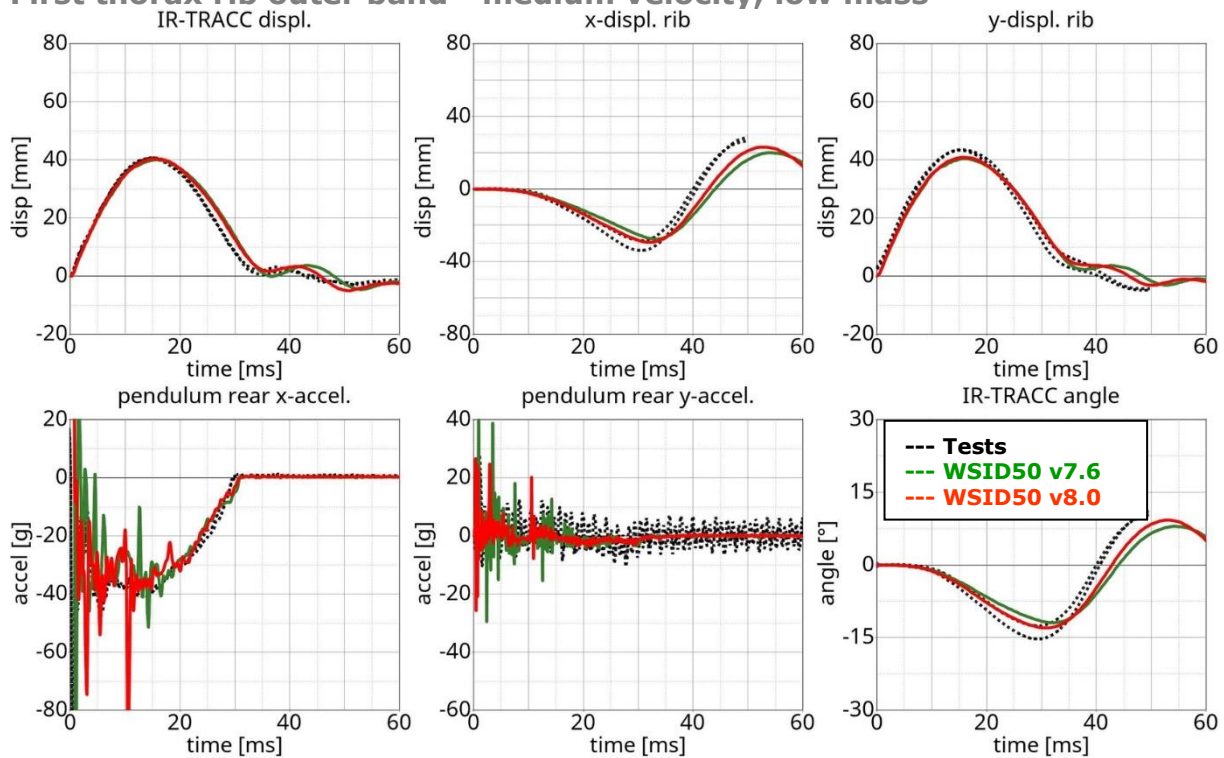


Figure 87: First thorax rib test on outer band - middle velocity and low mass

First thorax rib outer band - medium velocity, high mass

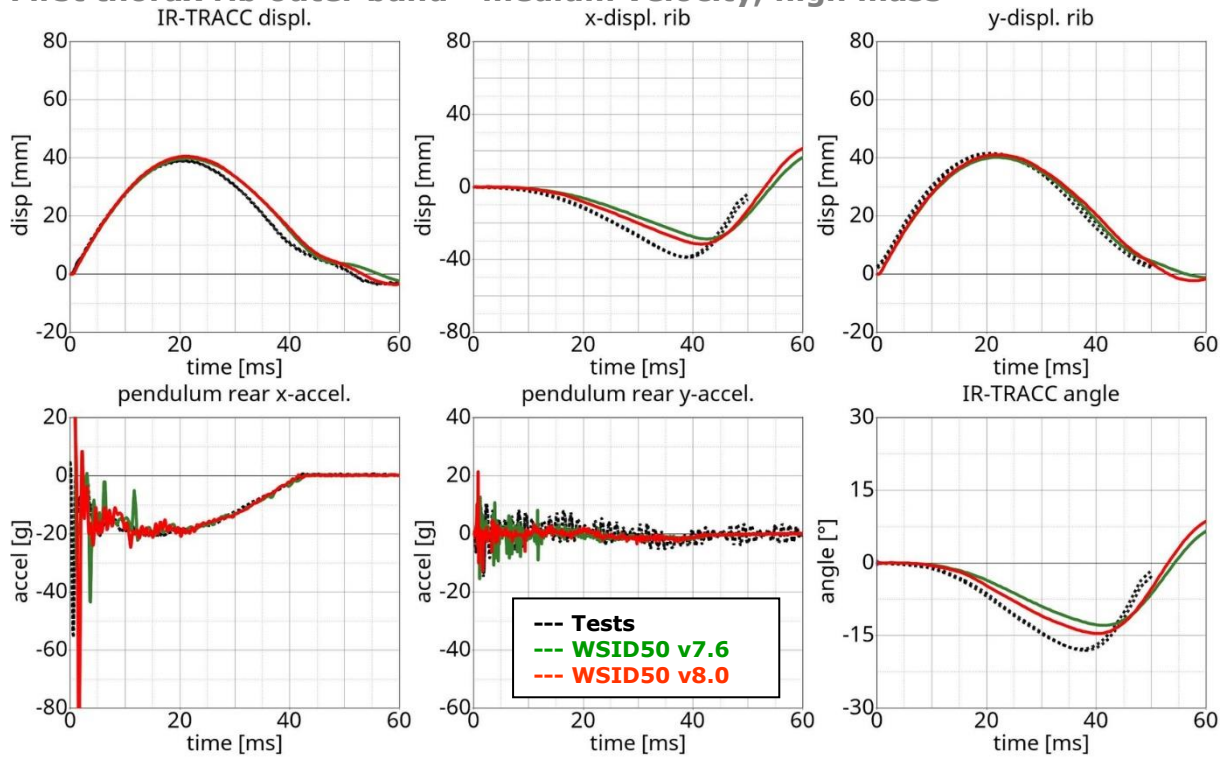


Figure 88: First thorax rib test on outer band - middle velocity and high mass

First thorax rib outer band - high velocity, low mass

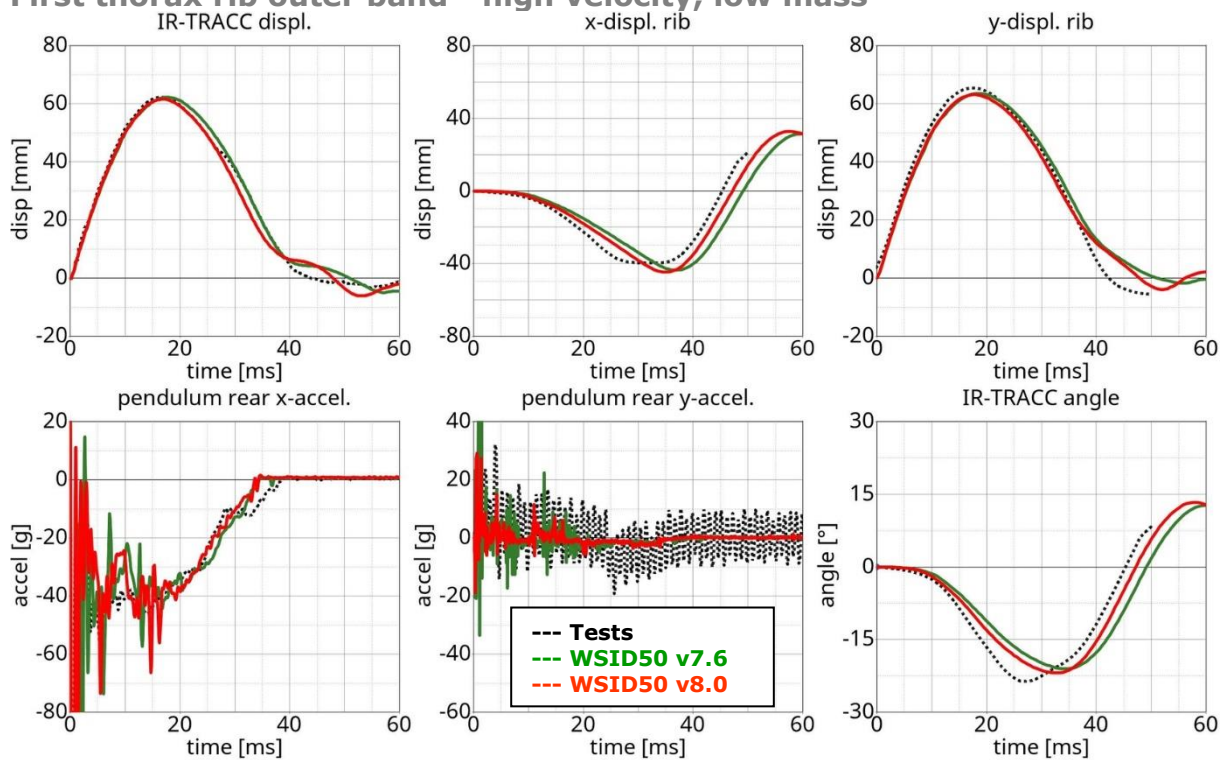


Figure 89: First thorax rib test on outer band - high velocity and low mass

First thorax rib outer band - high velocity, high mass

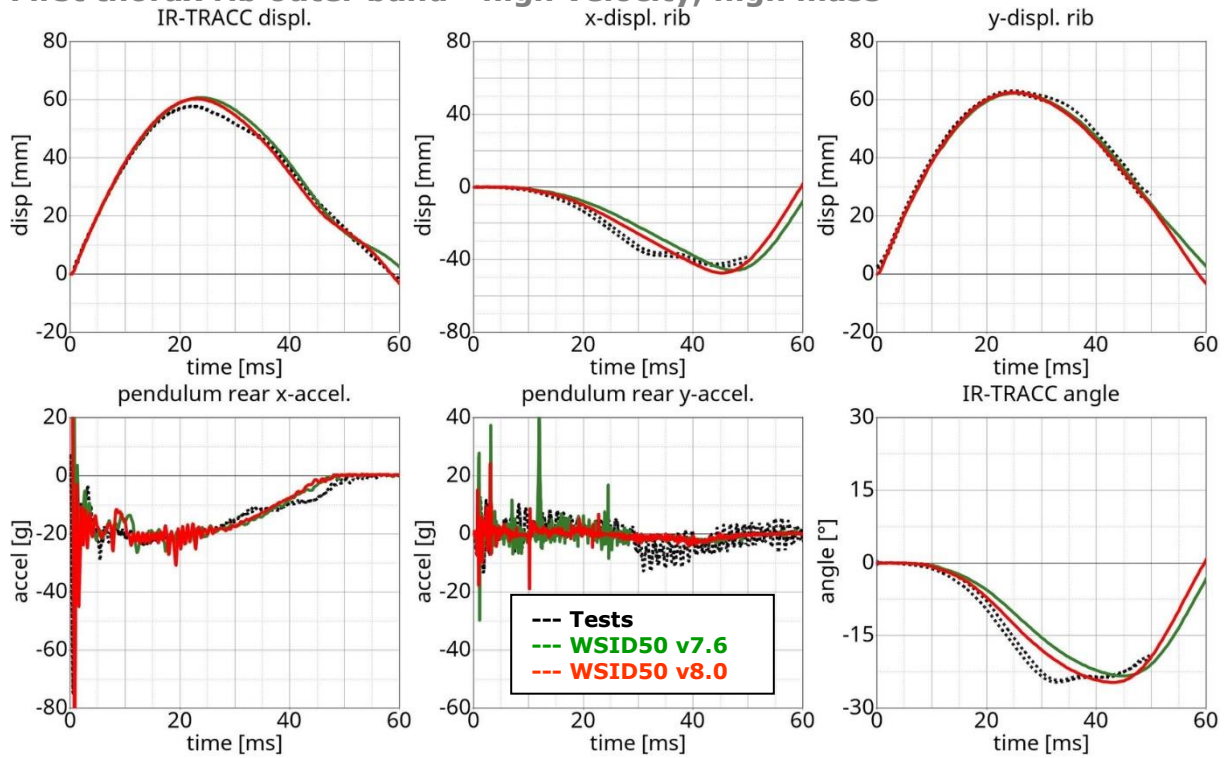


Figure 90: First thorax rib test on outer band - high velocity and high mass

Third thorax rib:

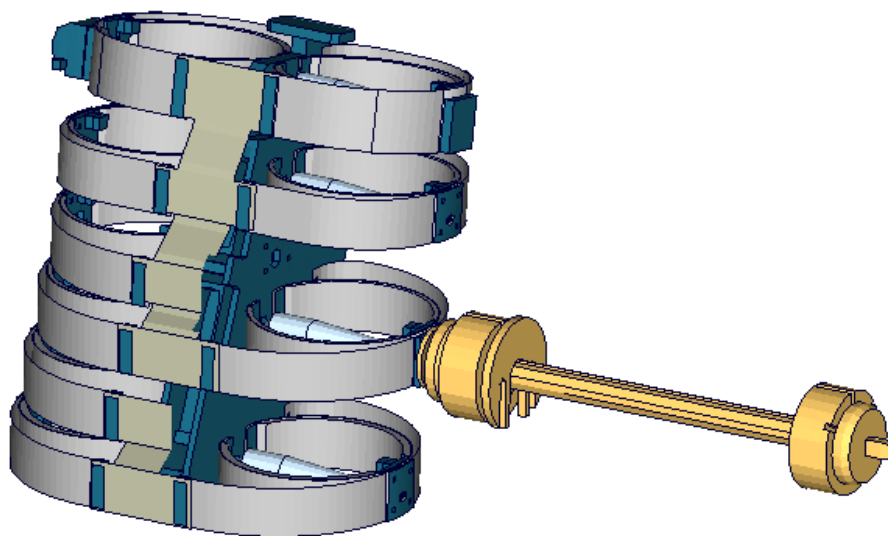


Figure 91: Third thorax rib outer band test

Third thorax rib outer band - low velocity, low mass

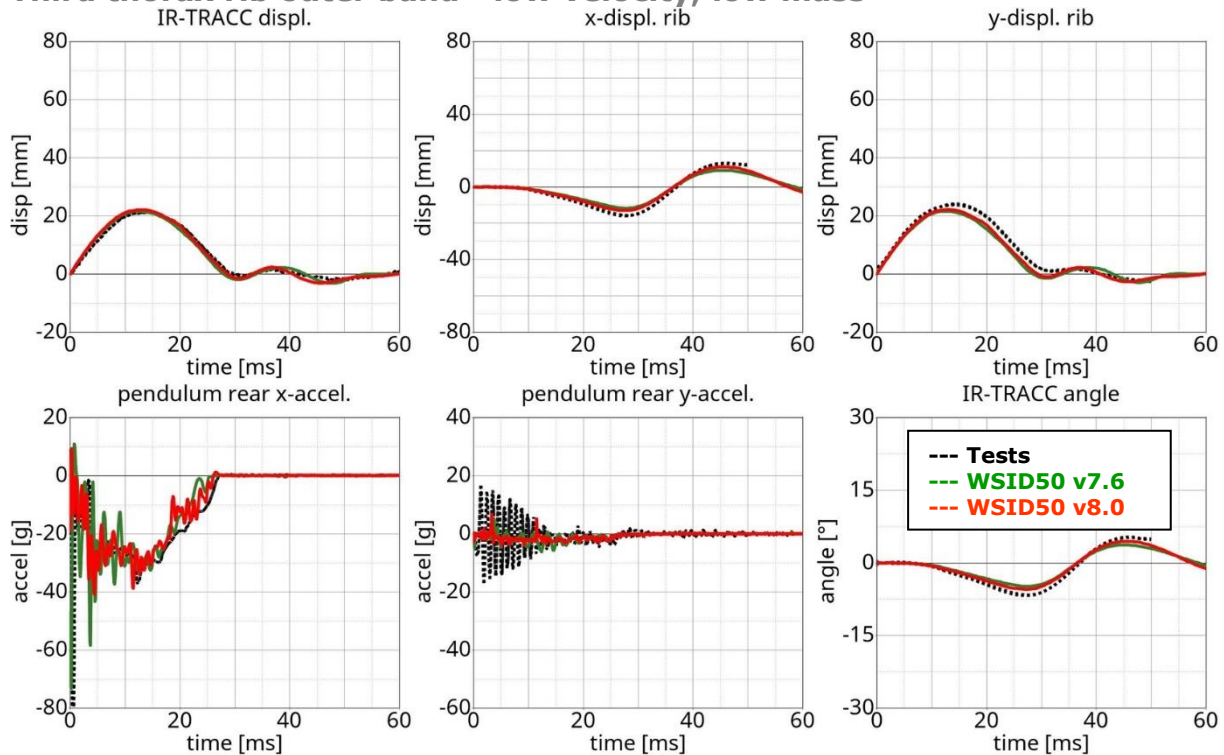


Figure 92: Third thorax rib test on outer band - low velocity and low mass

Third thorax rib outer band - low velocity, high mass

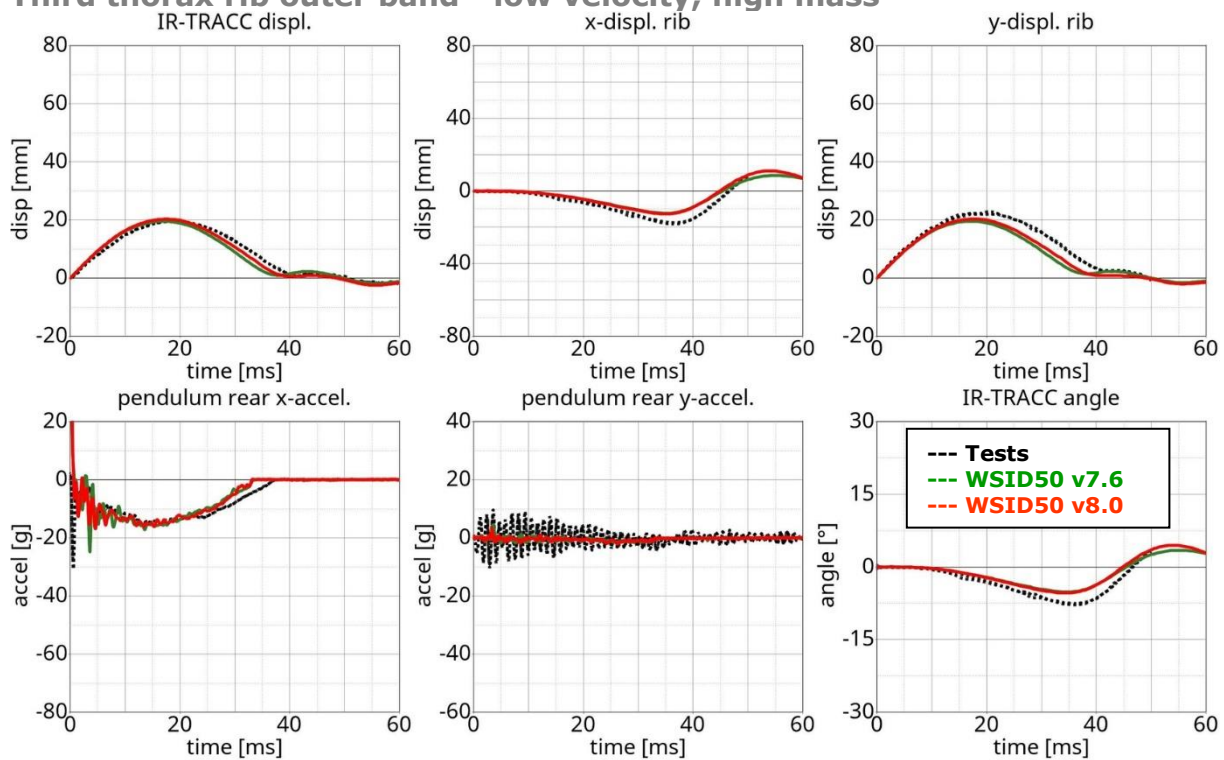


Figure 93: Third thorax rib test on outer band - low velocity and high mass

Third thorax rib outer band - medium velocity, low mass

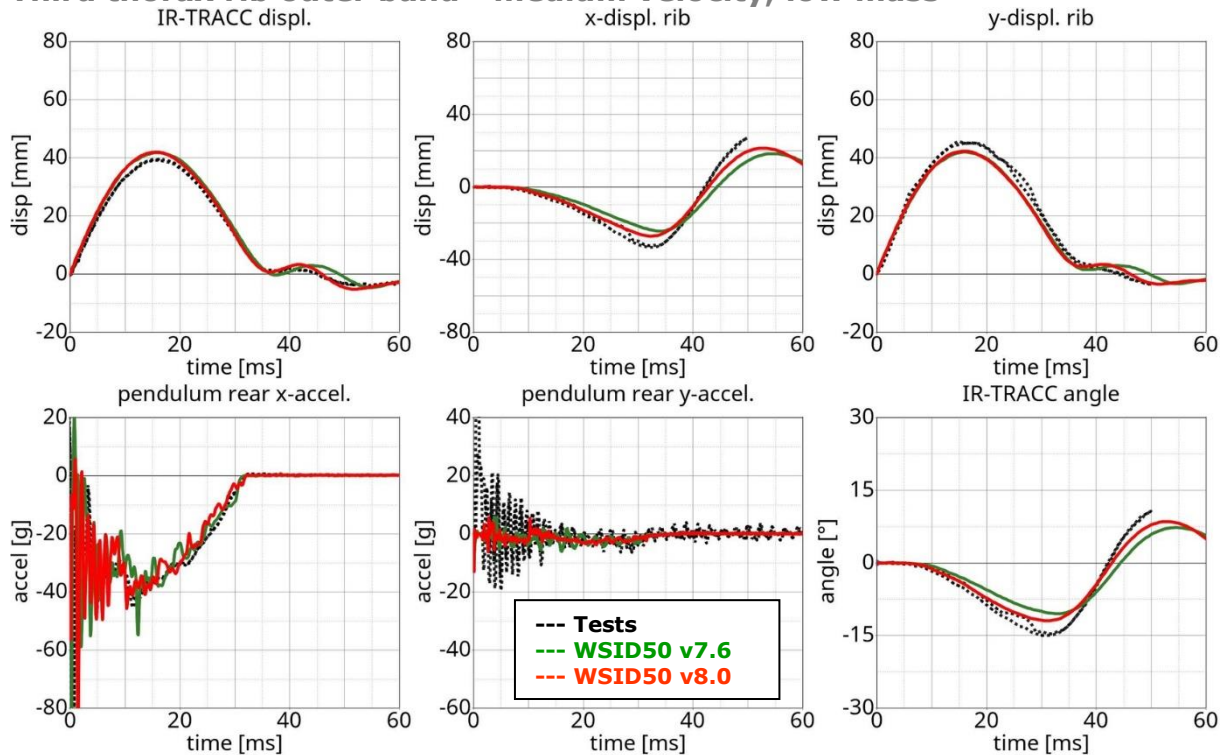


Figure 94: Third thorax rib test on outer band - medium velocity and low mass

Third thorax rib outer band - medium velocity, high mass

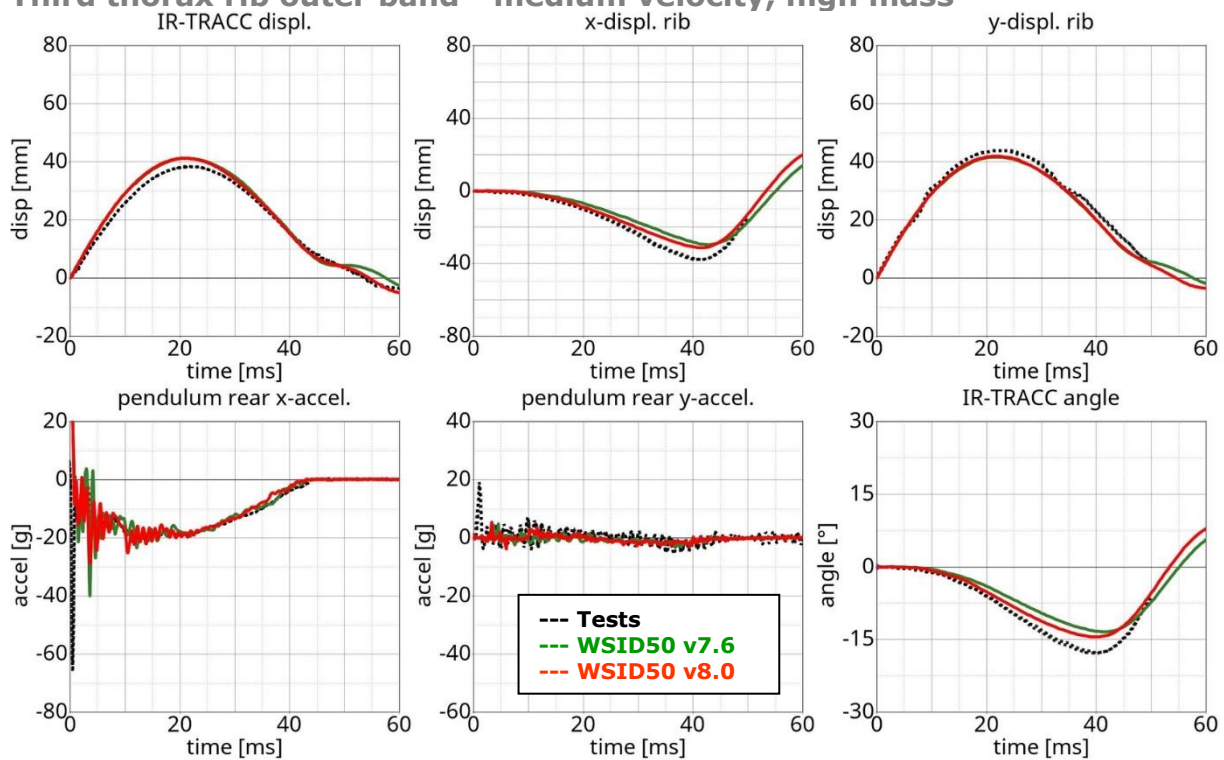


Figure 95: third thorax rib test on outer band - medium velocity and high mass

Third thorax rib outer band - high velocity, low mass

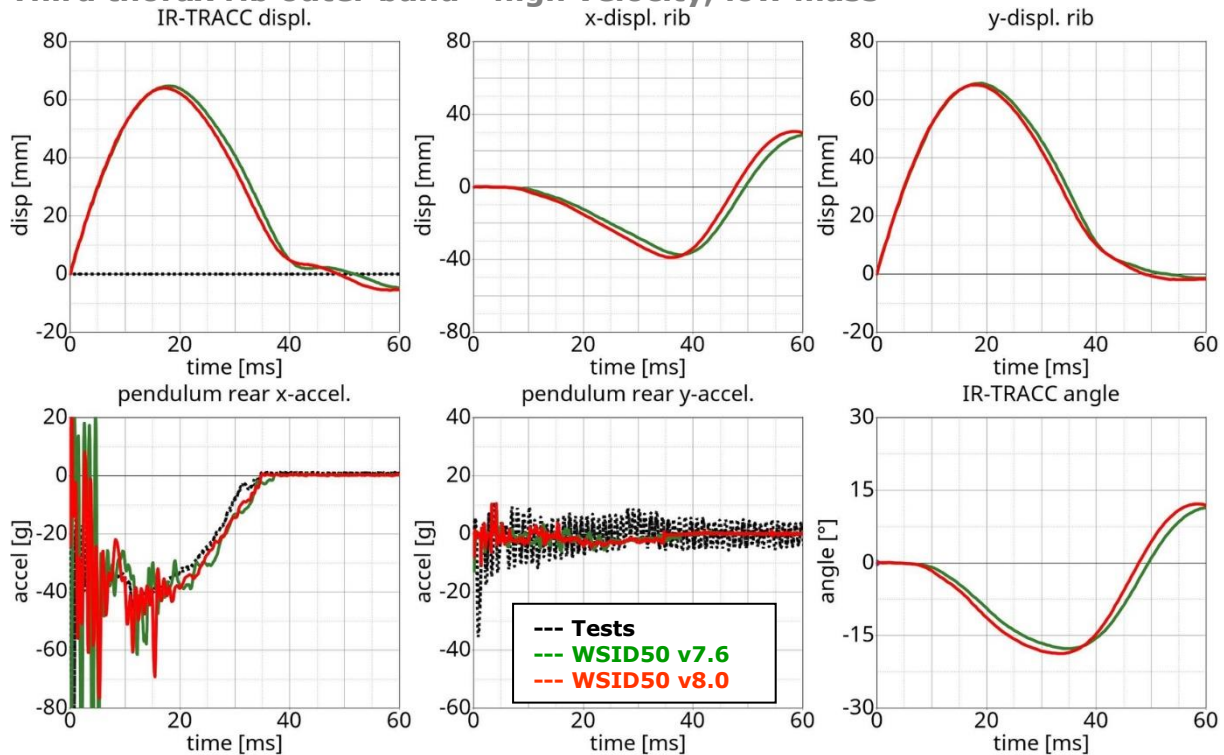


Figure 96: Third thorax rib test on outer band - high velocity and low mass

Third thorax rib outer band - high velocity, high mass

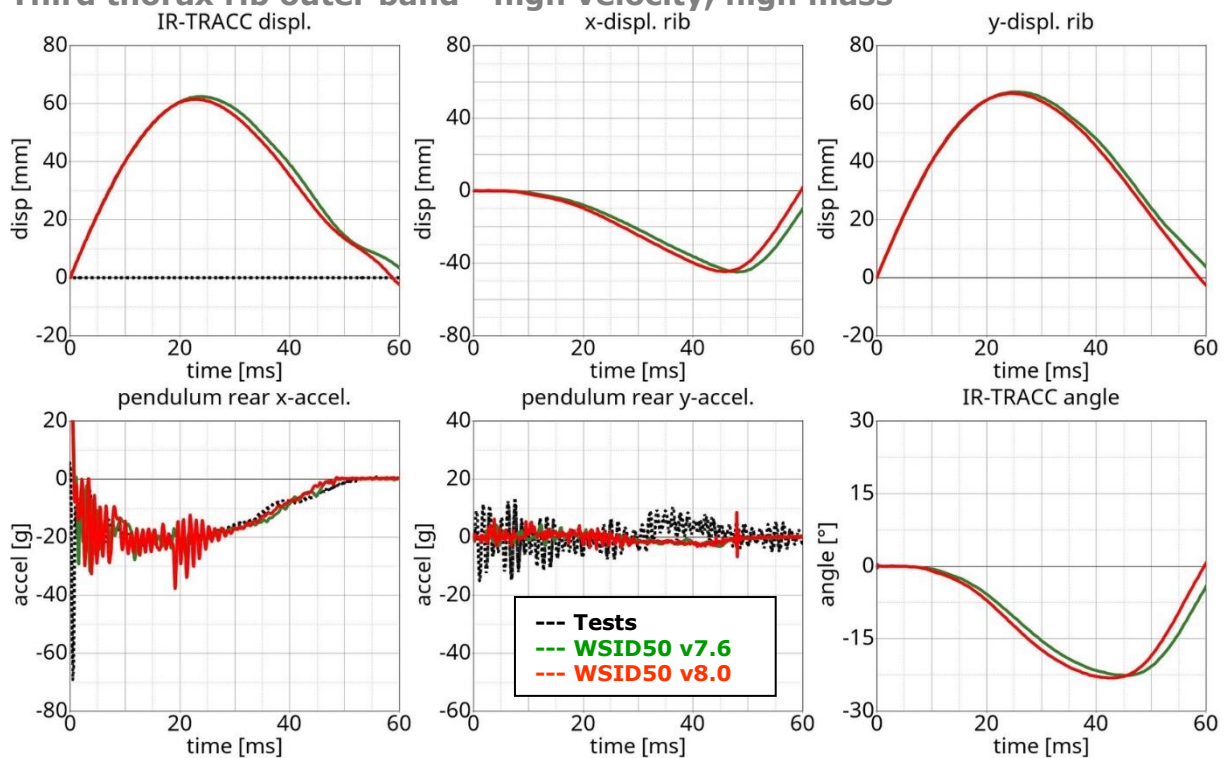


Figure 97: third thorax rib test on outer band - high velocity and high mass

Second abdomen rib:

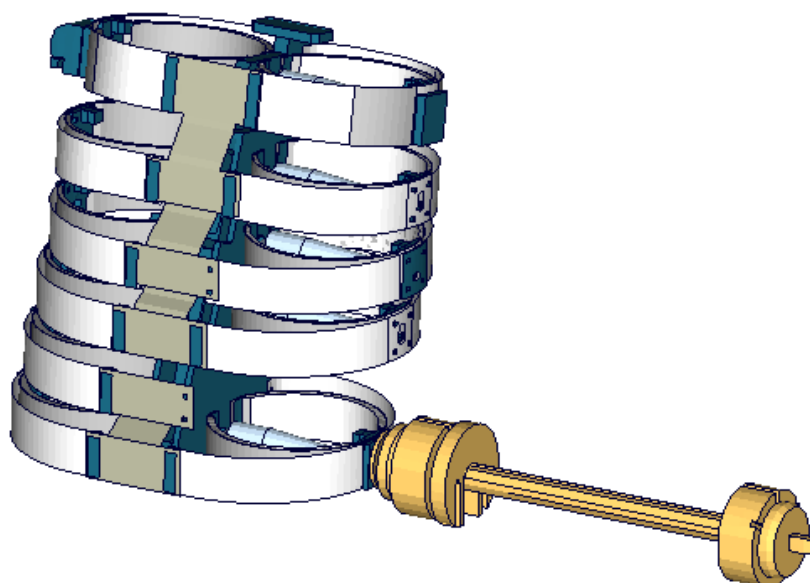


Figure 98: Second abdomen rib outer band test

Second abdomen rib outer band - low velocity, low mass

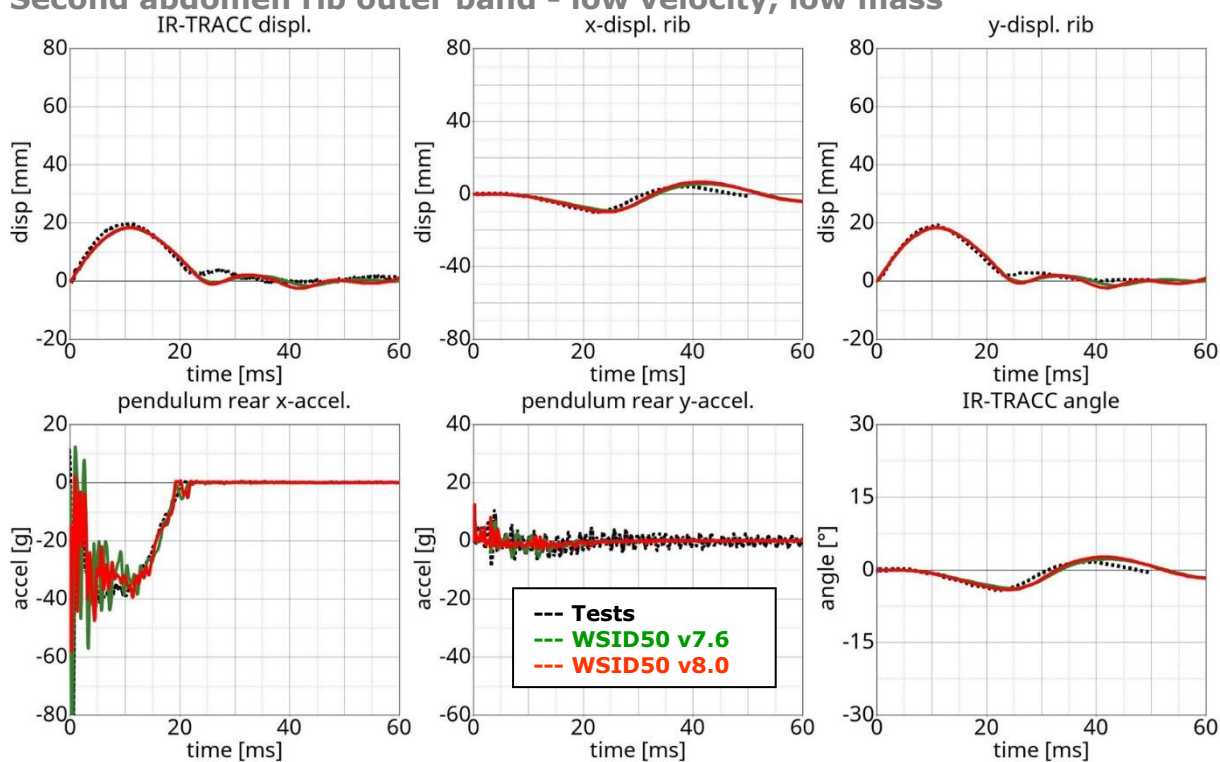


Figure 99: Second abdomen rib test on outer band - low velocity and low mass

Second abdomen rib outer band - low velocity, high mass

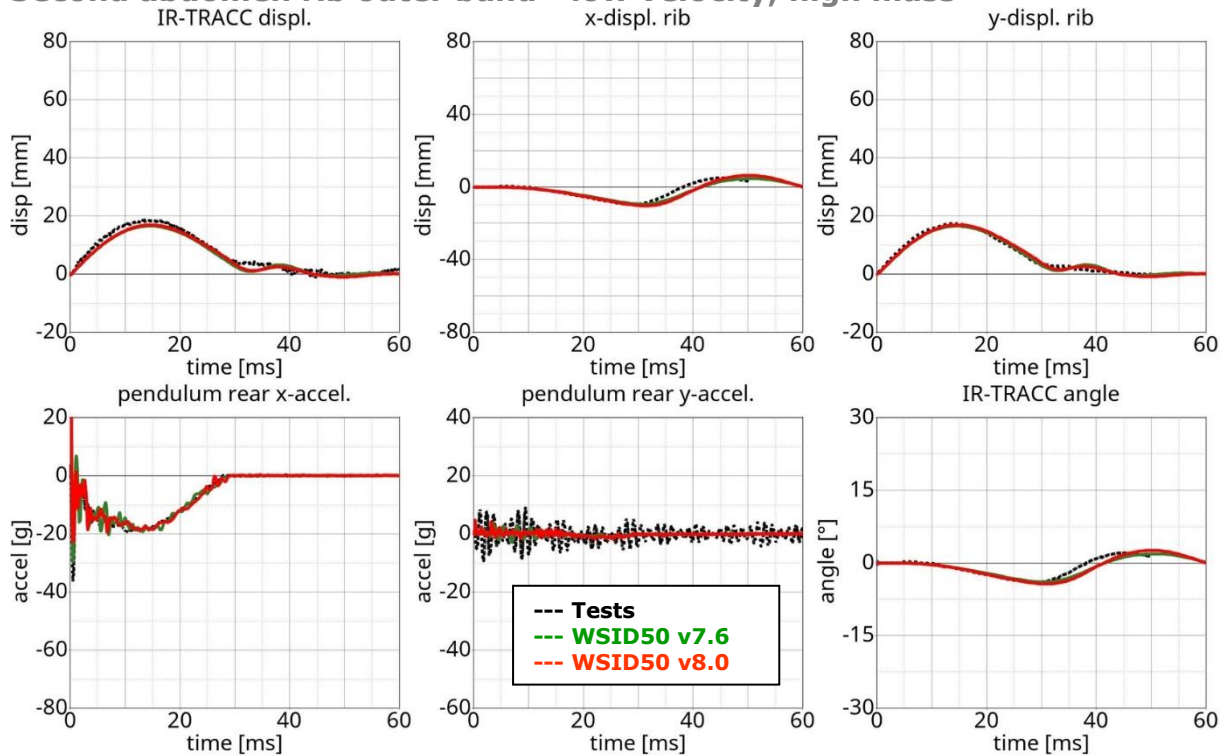


Figure 100: Second abdomen rib test on outer band - low velocity and high mass

Second abdomen rib outer band - medium velocity, low mass

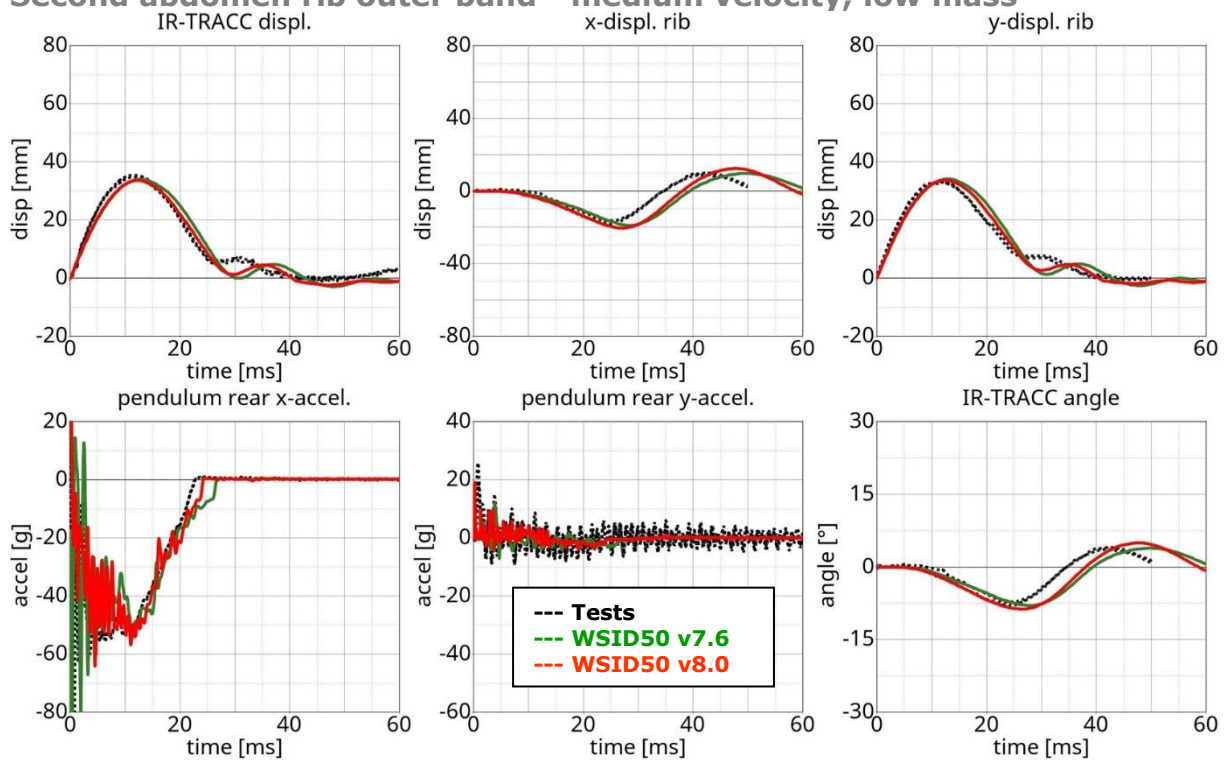


Figure 101: Second abdomen rib test on outer band - middle velocity and low mass

Second abdomen rib outer band - medium velocity, high mass

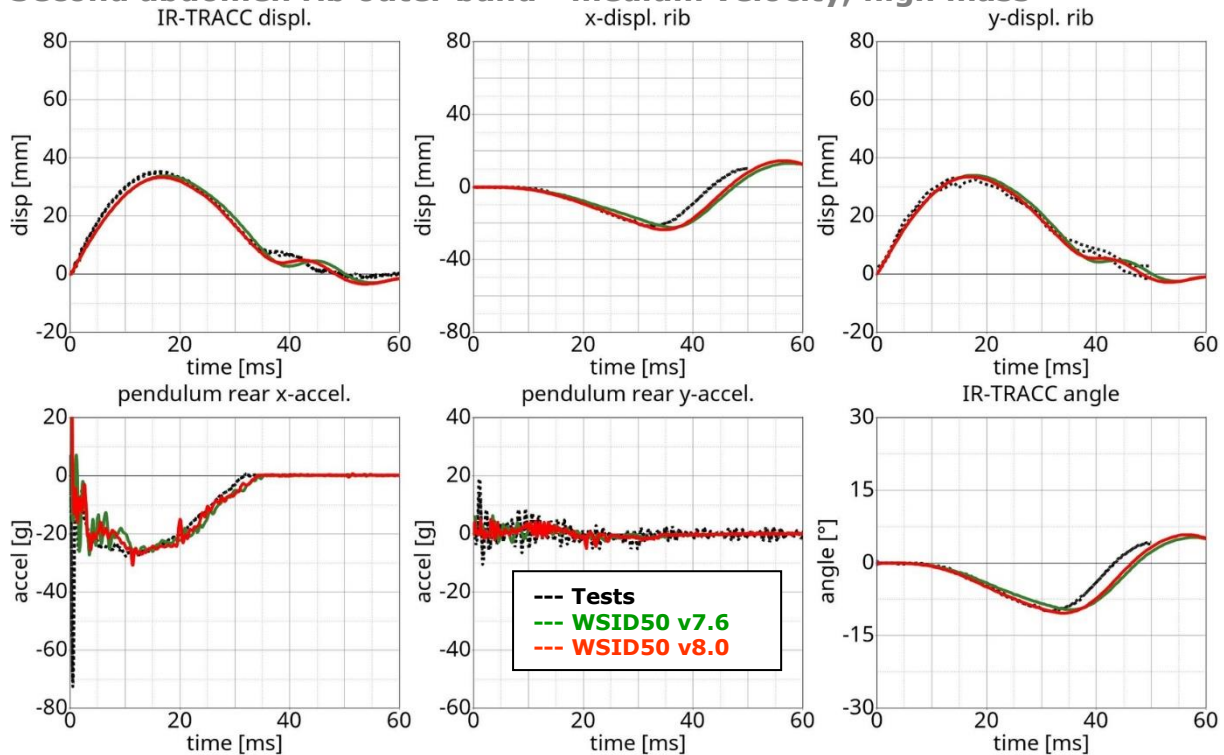


Figure 102: Second abdomen rib test on outer band - middle velocity and high mass

Second abdomen rib outer band - high velocity, low mass

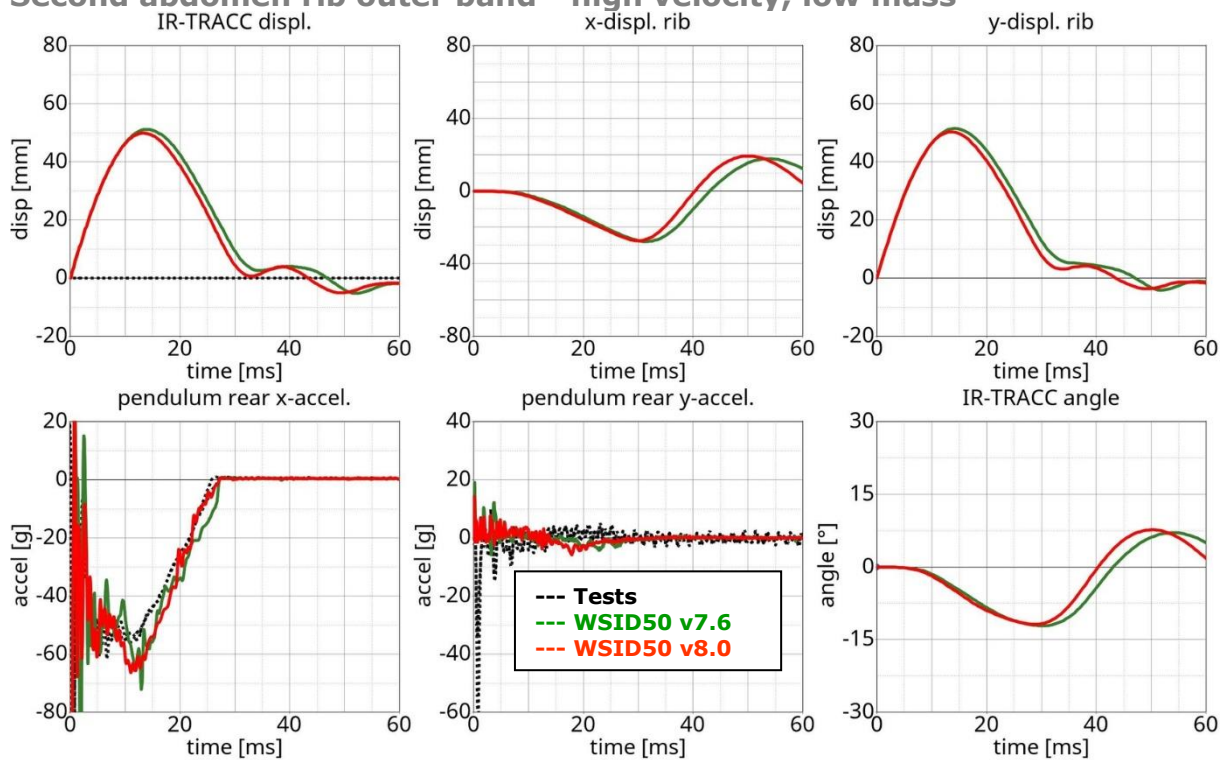


Figure 103: Second abdomen rib test on outer band - high velocity and low mass

Second abdomen rib outer band - high velocity, high mass

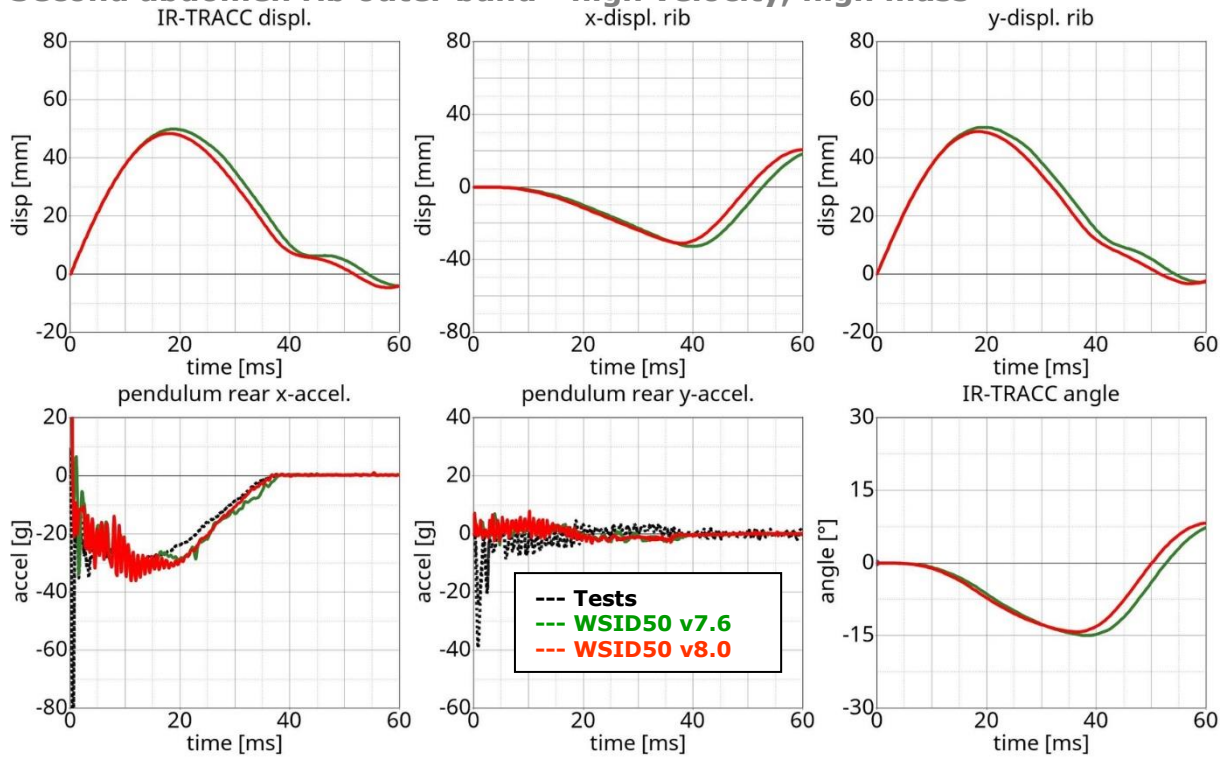


Figure 104: Second abdomen rib test on outer band - high velocity and high mass

Additional second abdomen rib test:

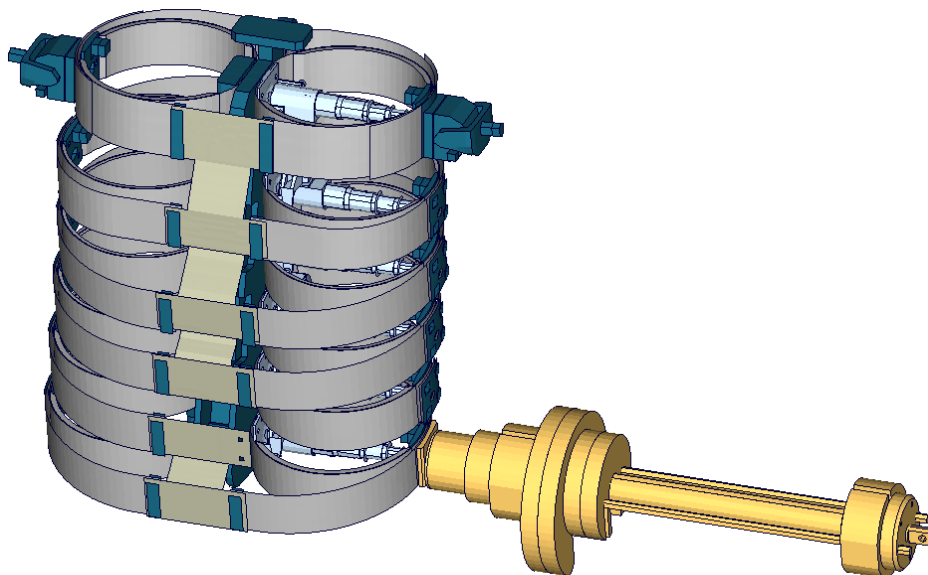


Figure 105: Second abdomen rib additional test

Second abdomen rib additional - high velocity

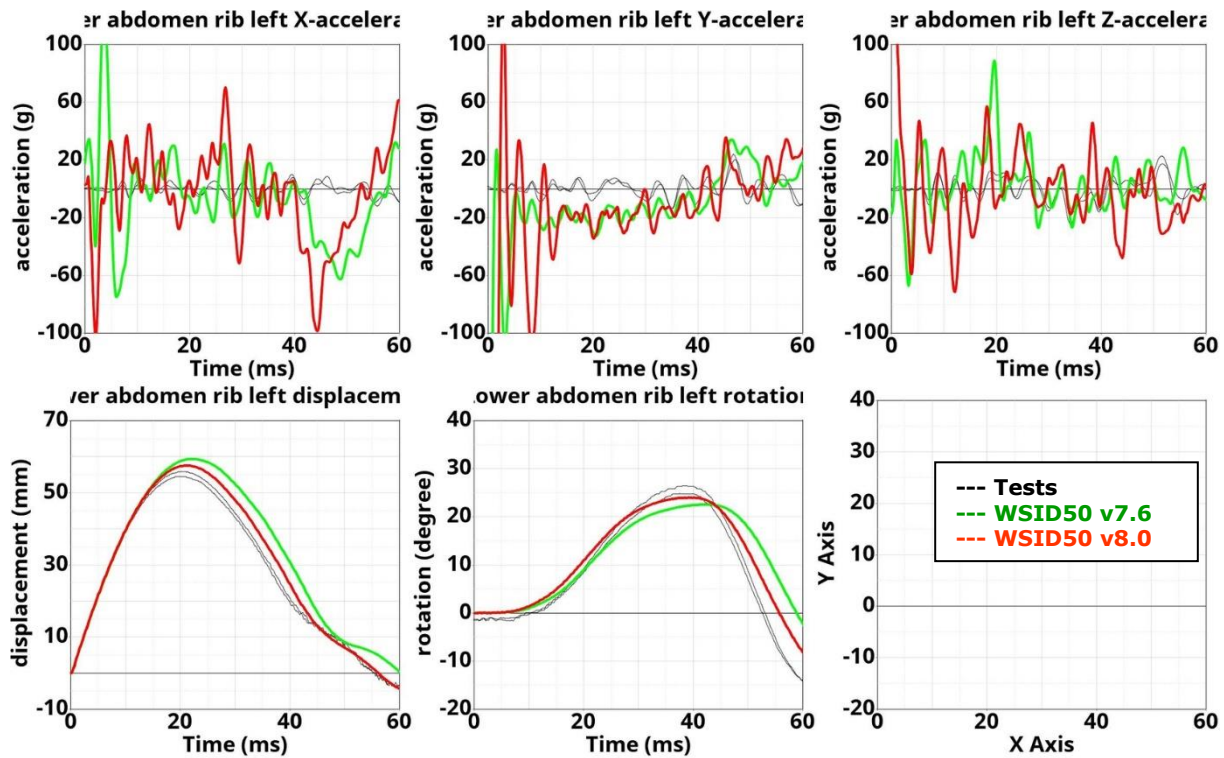


Figure 106: Second abdomen rib test on outer band - high velocity and high mass

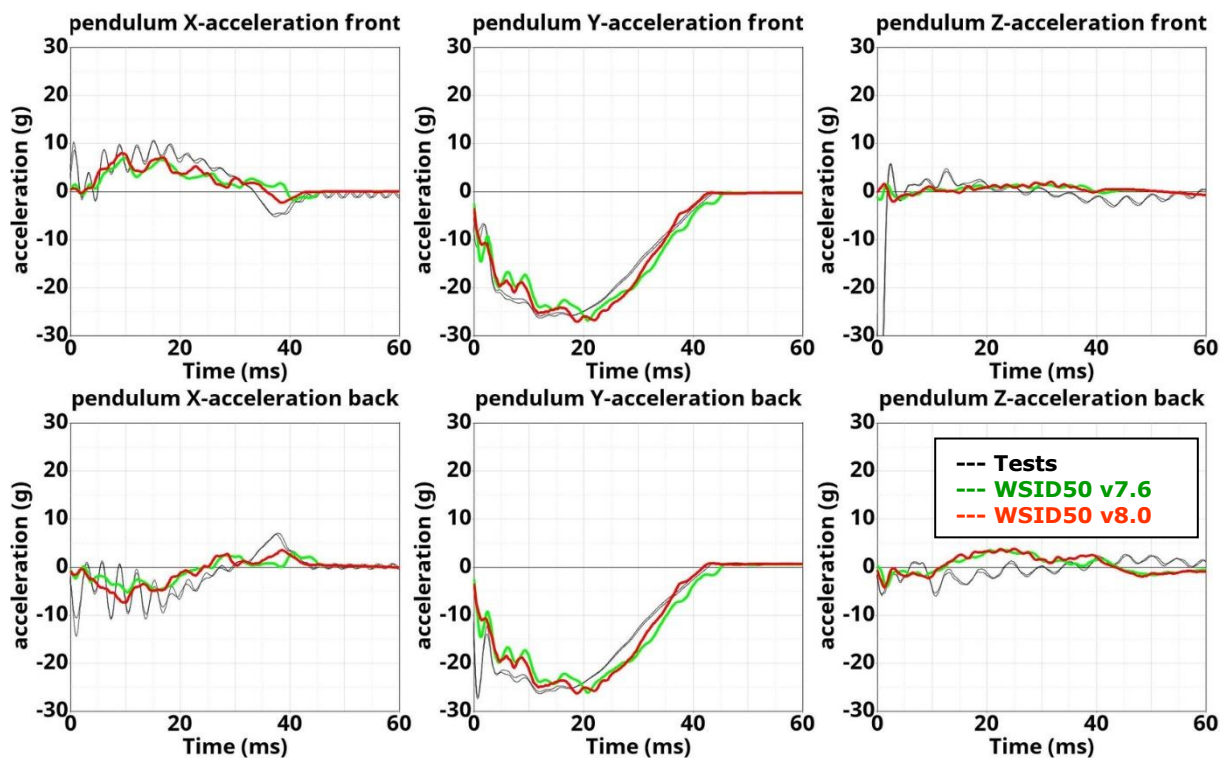


Figure 107: Second abdomen rib test on outer band - high velocity and high mass

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.

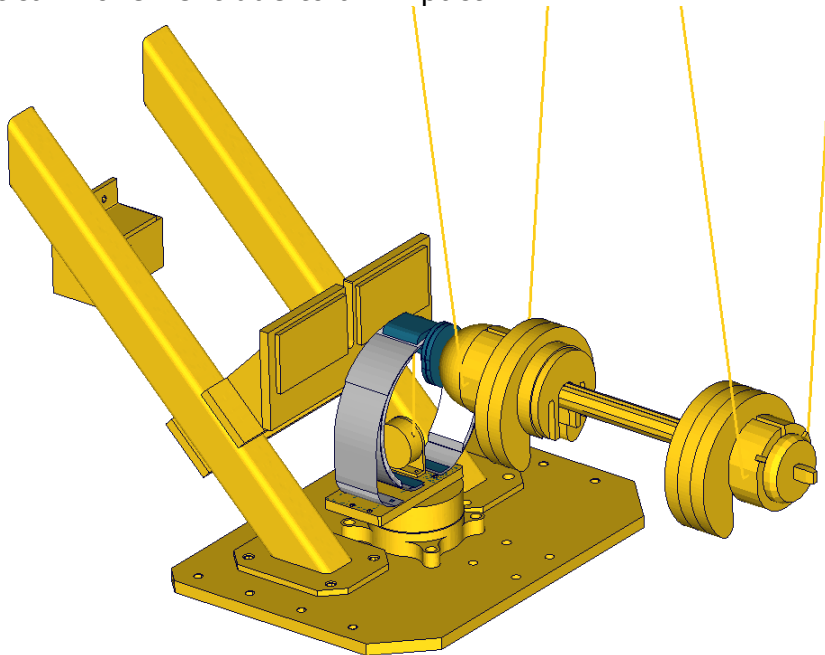


Figure 108: shoulder rib tests in z-direction

Shoulder rib outer band z-direction - low velocity

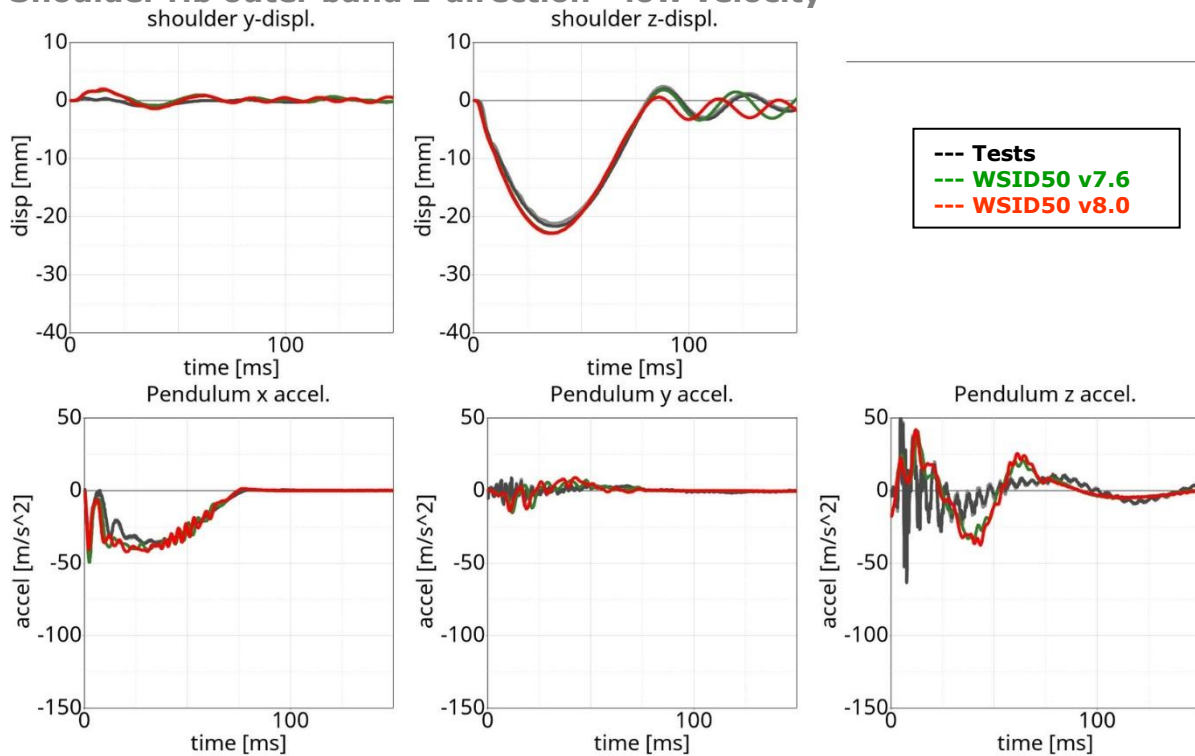


Figure 109: shoulder rib test on outer band z-direction – low velocity

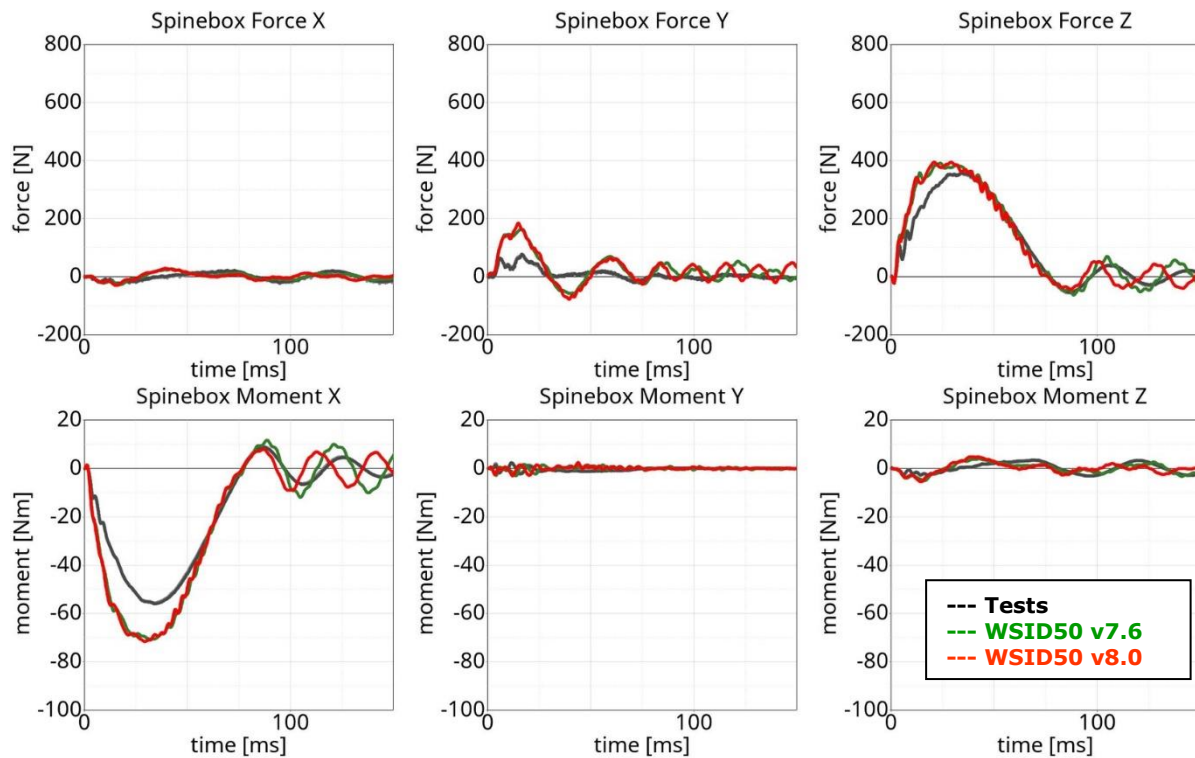


Figure 110: shoulder rib test on outer band z-direction – low velocity

Shoulder rib outer band z-direction - medium velocity

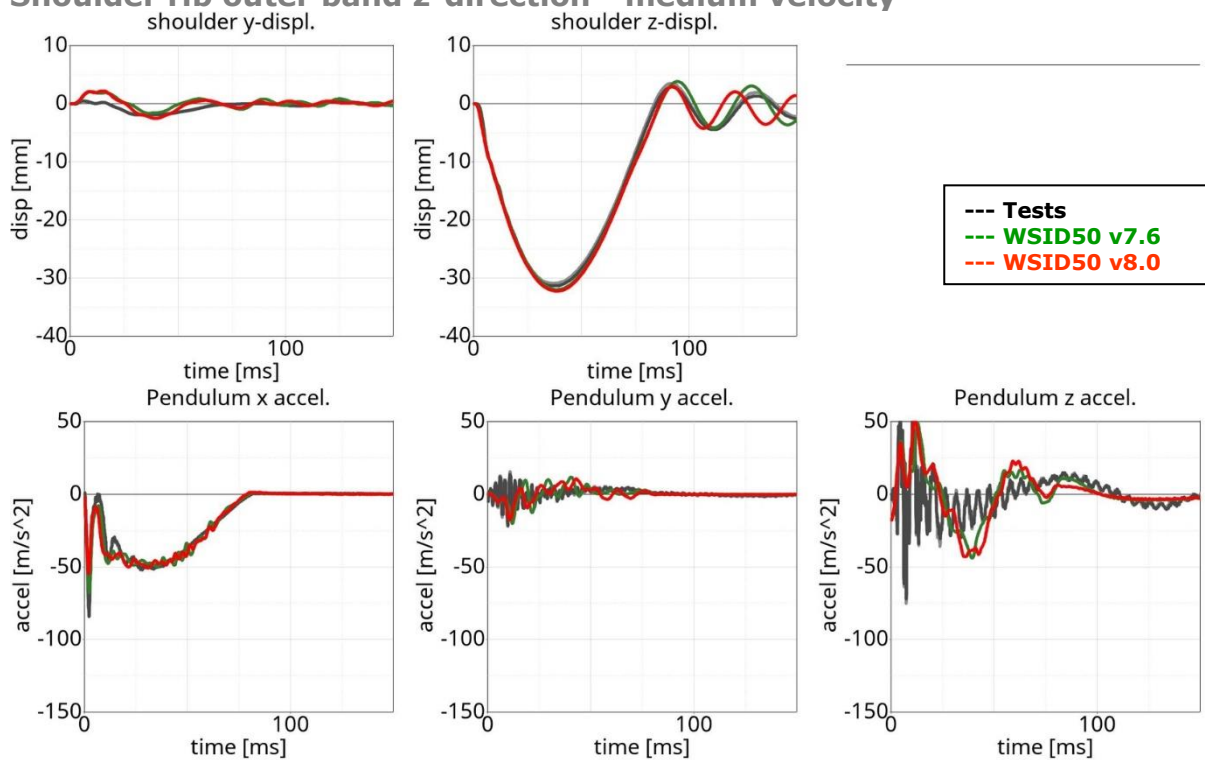


Figure 111: shoulder rib test on outer band z-direction – medium velocity

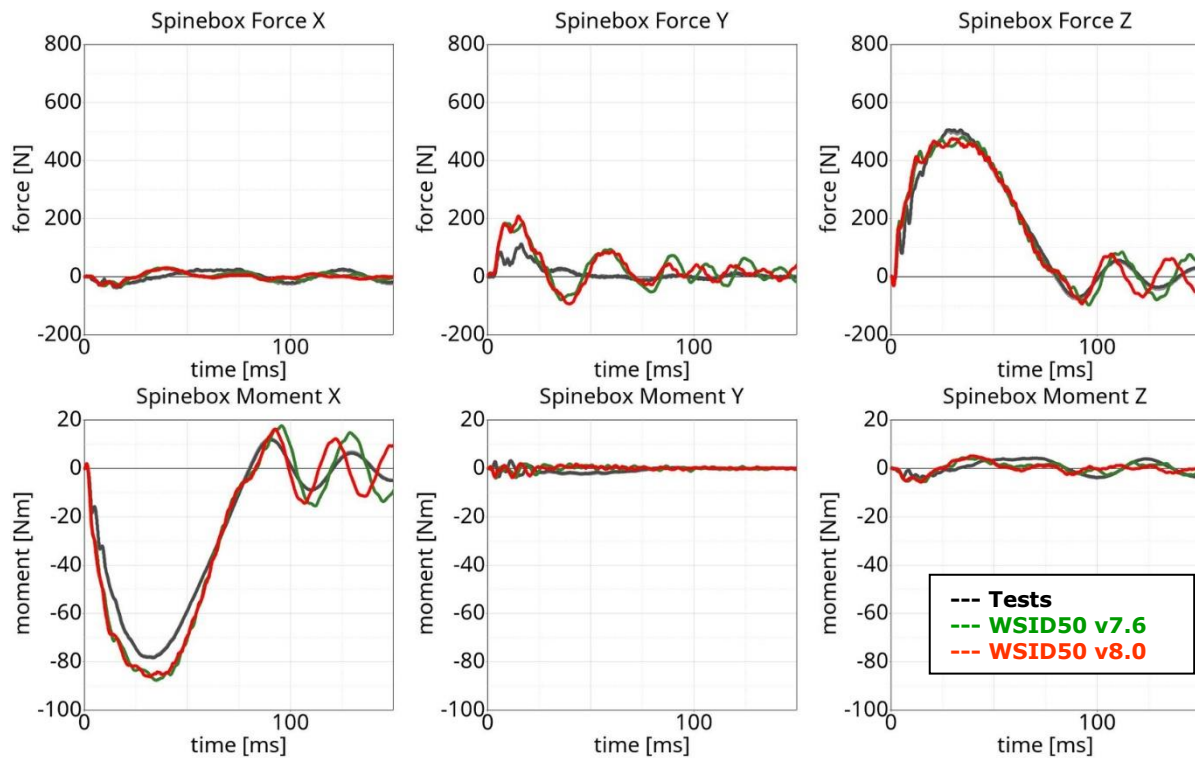


Figure 112: shoulder rib test on outer band z-direction – medium velocity

Shoulder rib outer band z-direction - high velocity

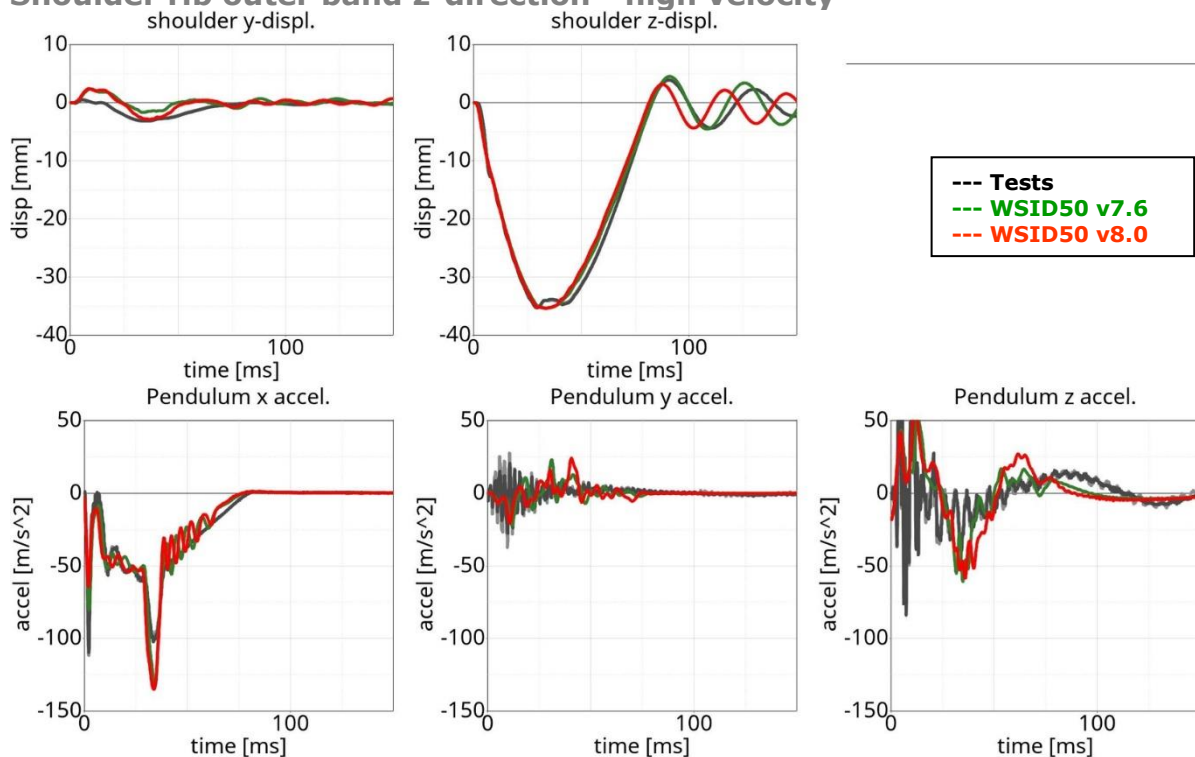


Figure 113: shoulder rib test on outer band z-direction – high velocity

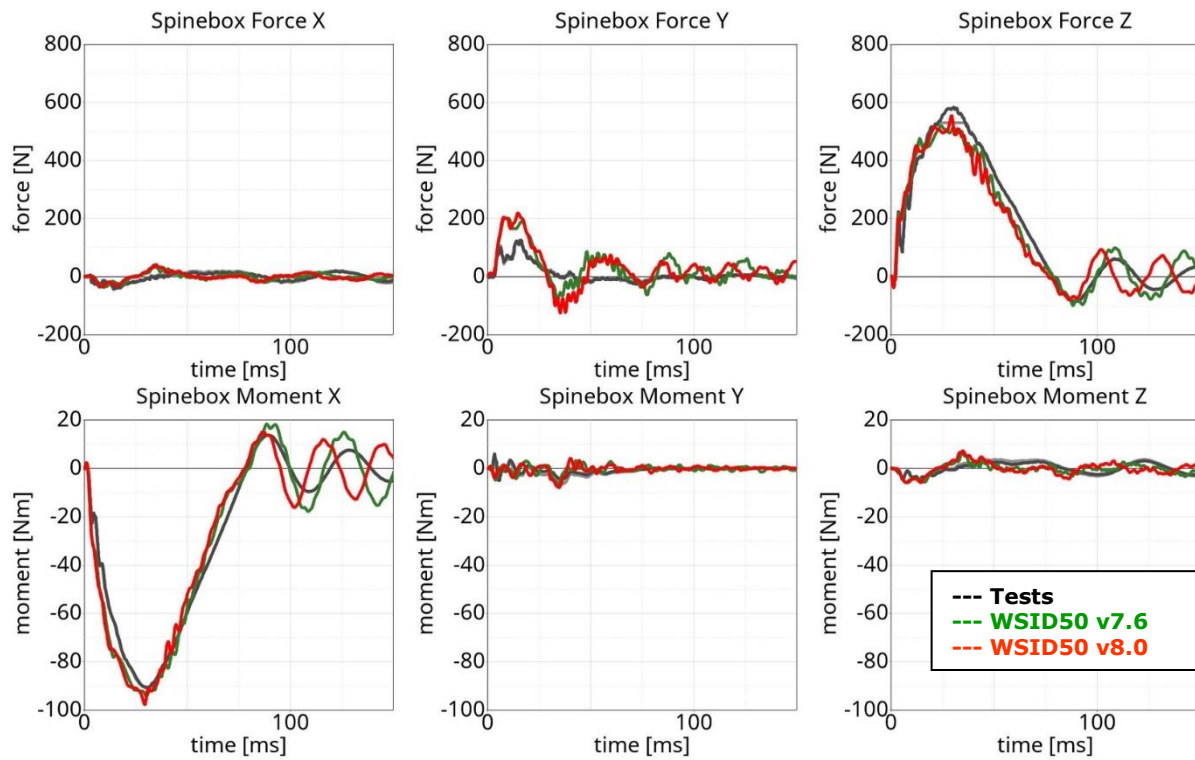


Figure 114: shoulder rib test on outer band z-direction – high velocity

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.

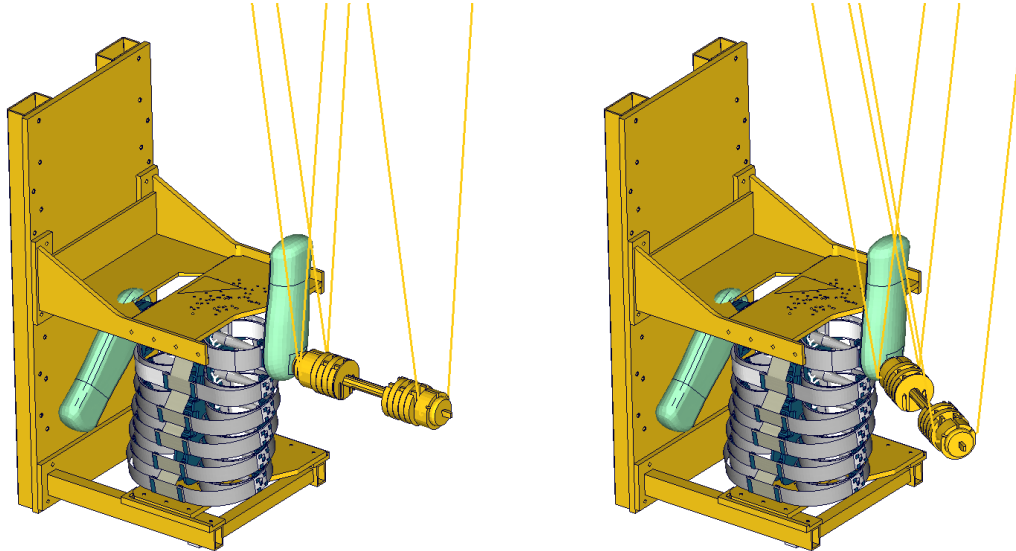


Figure 115: shoulder rib tests with arm (90° on the right and 60° on the left)

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

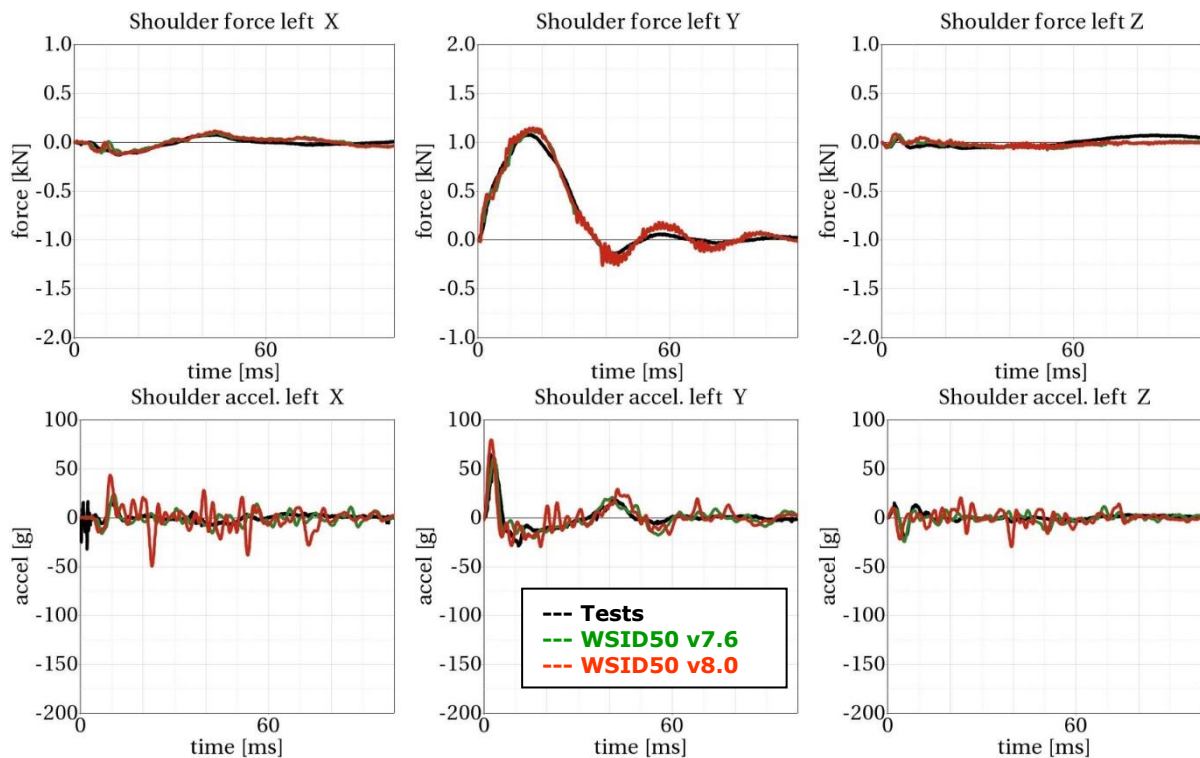


Figure 116: shoulder rib test on outer band with arm – low velocity, 90°

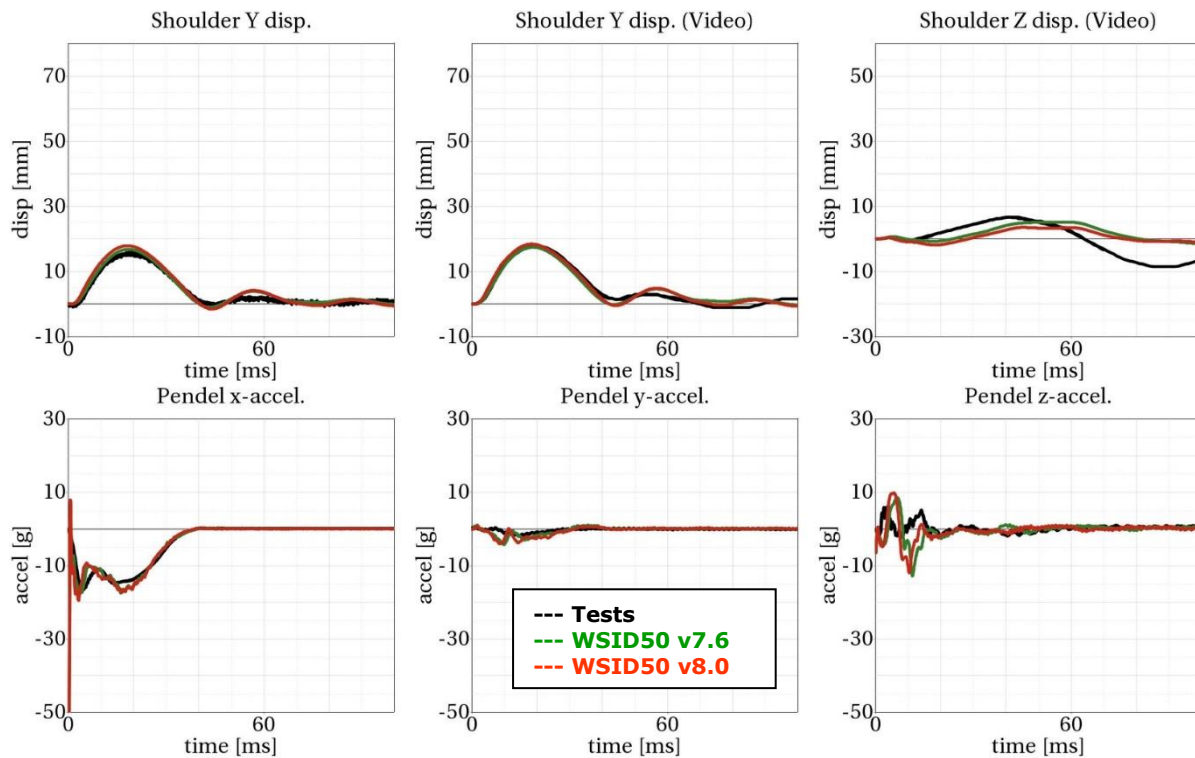


Figure 117: shoulder rib test on outer band with arm – low velocity, 90°

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

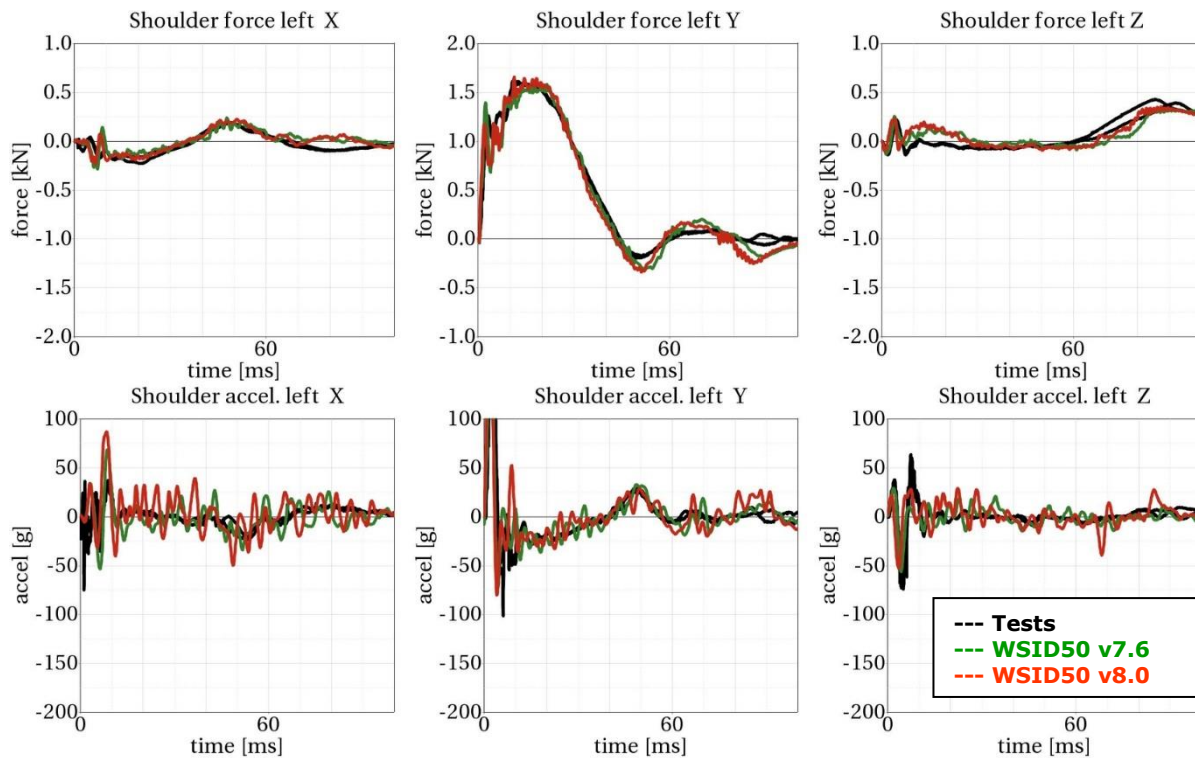


Figure 118: shoulder rib test on outer band with arm - high velocity, 90°

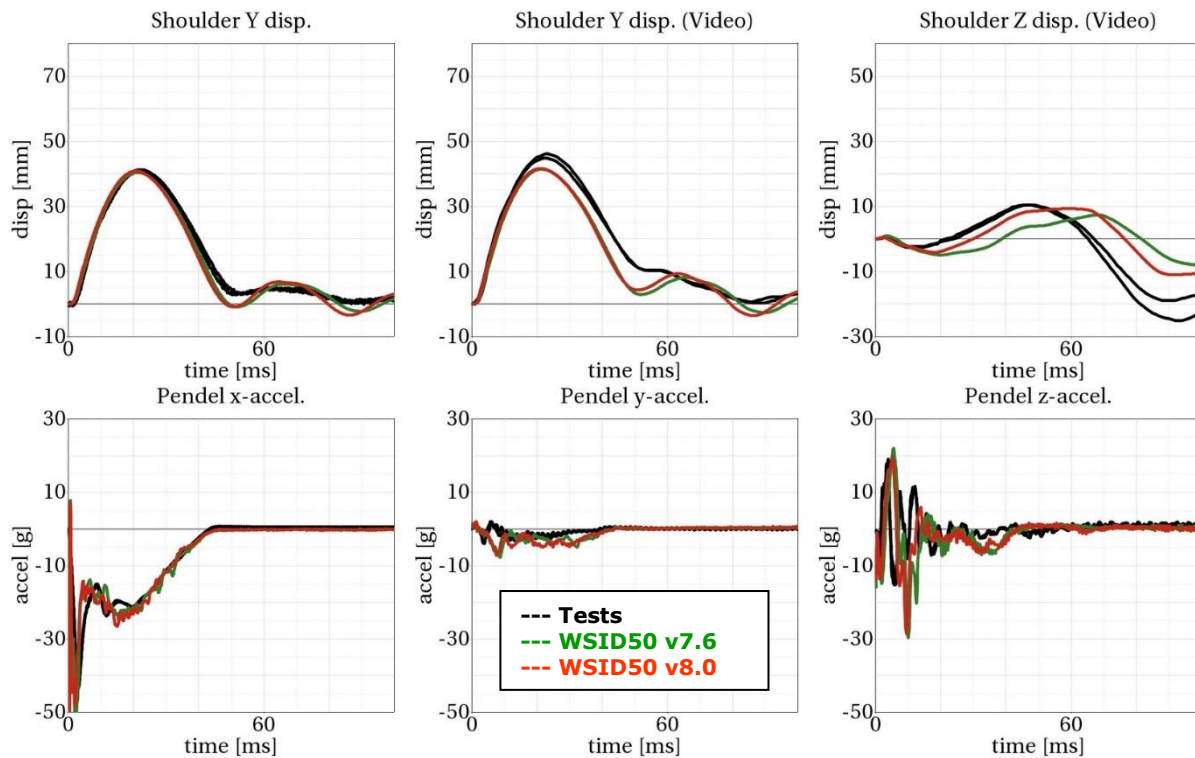


Figure 119: shoulder rib test on outer band with arm - high velocity, 90°

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

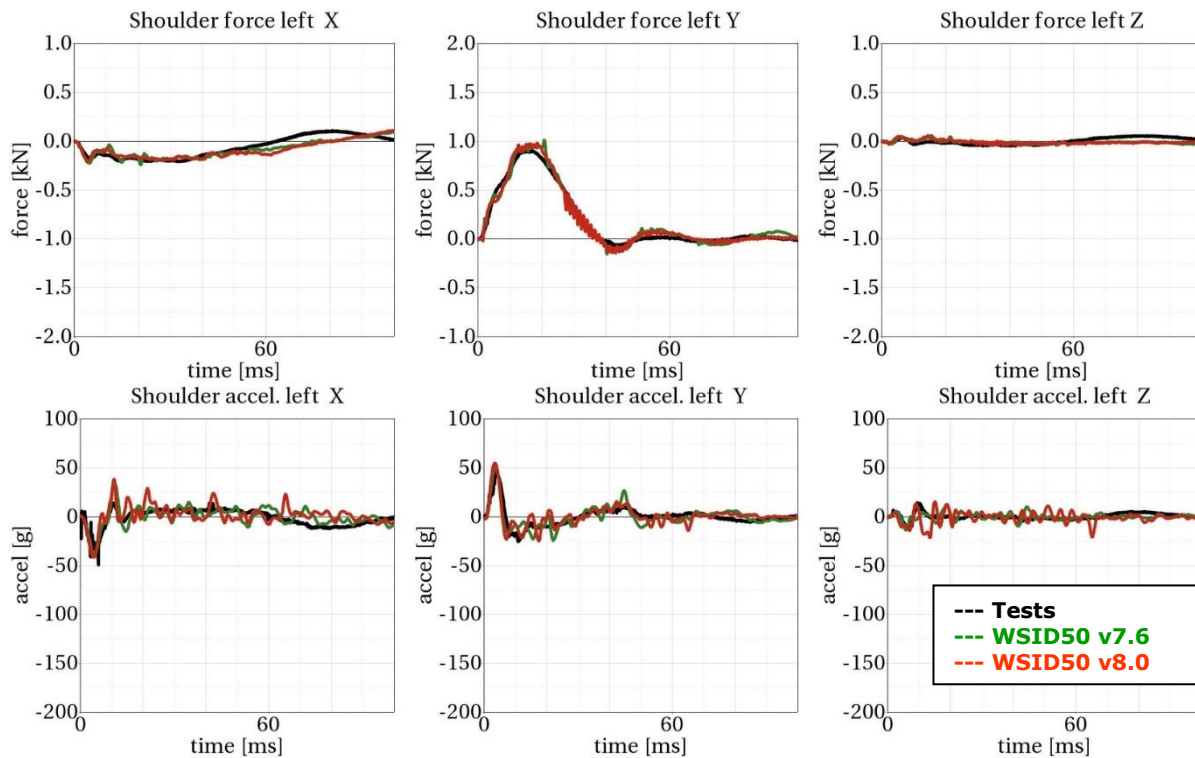


Figure 120: shoulder rib test on outer band with arm – low velocity, 60°

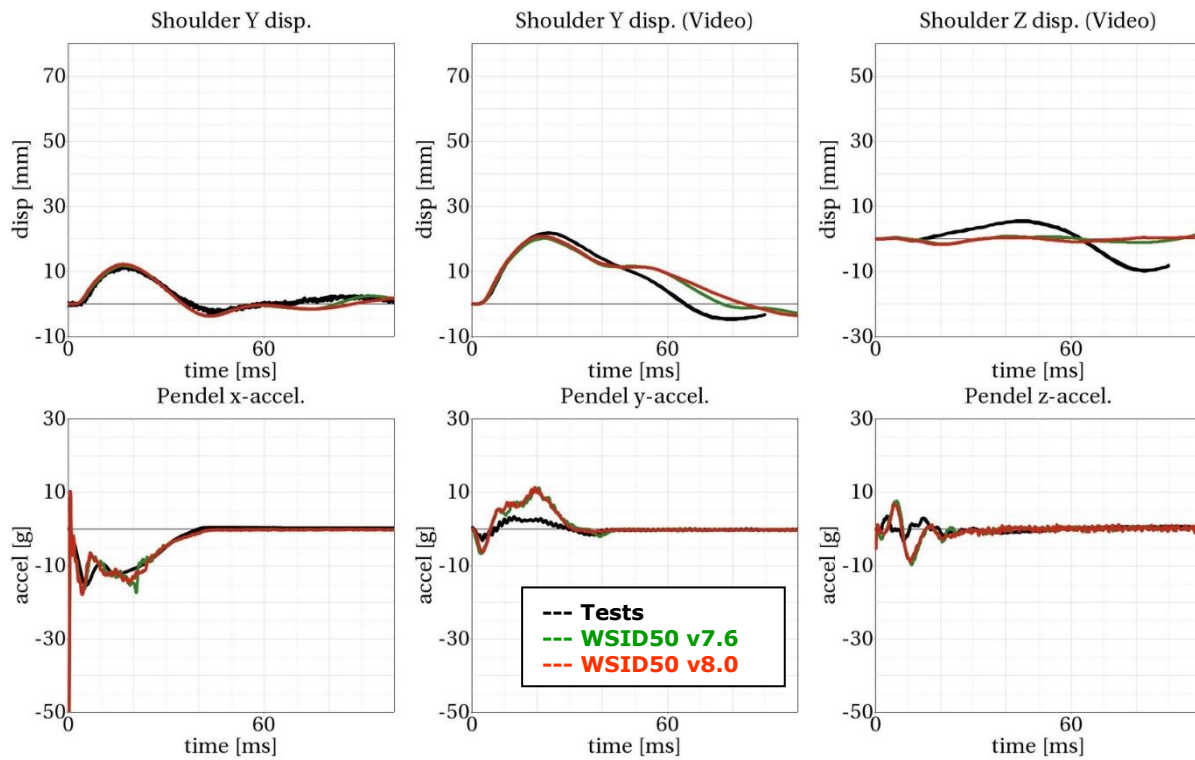


Figure 121: shoulder rib test on outer band with arm – low velocity, 60°

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

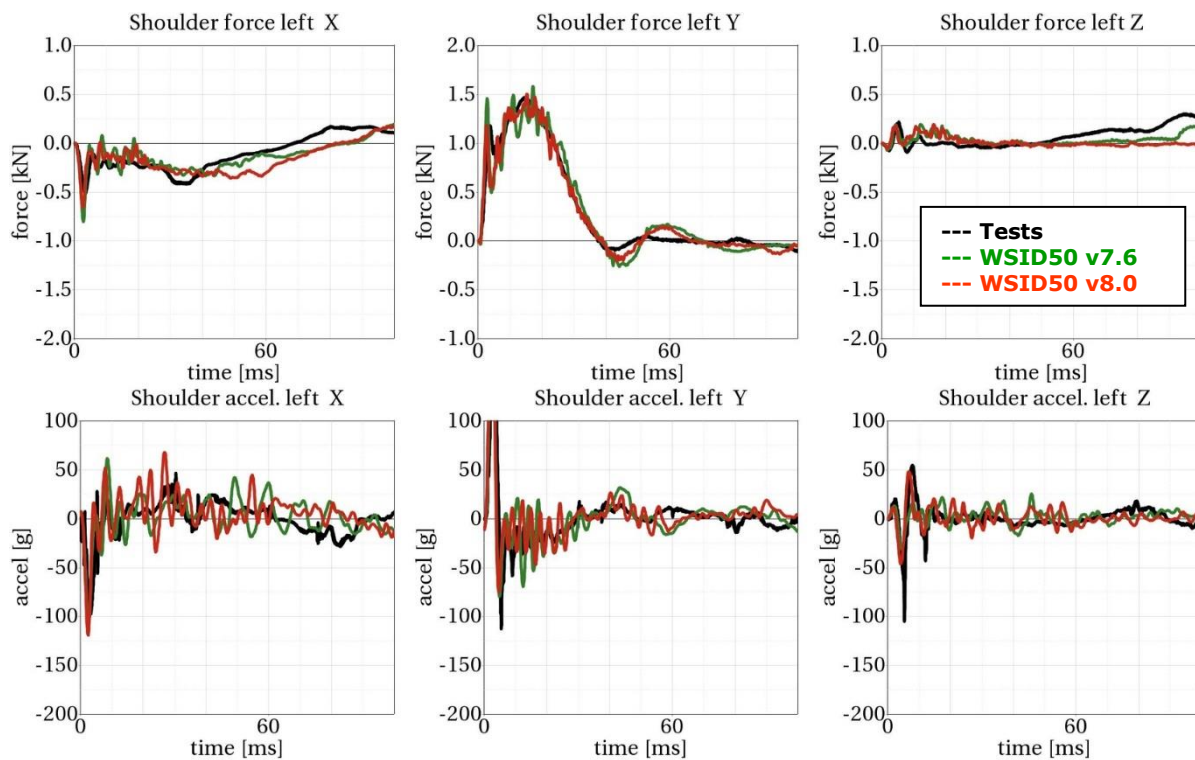


Figure 122: shoulder rib test on outer band with arm - high velocity, 60°

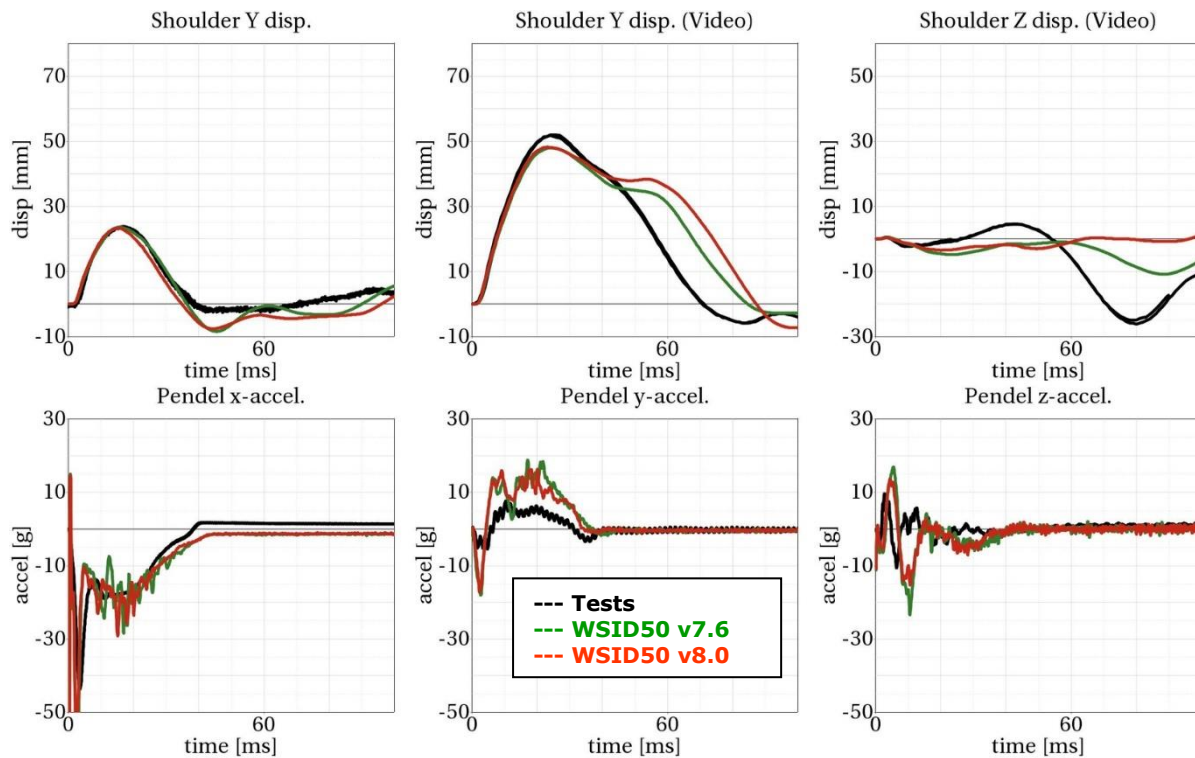


Figure 123: shoulder rib test on outer band with arm - high velocity, 60°

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.

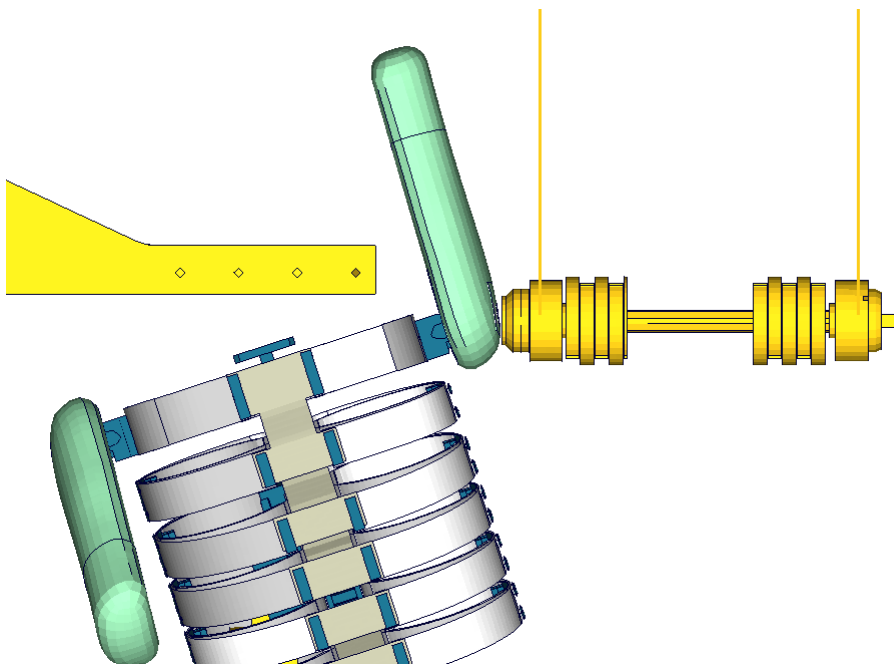


Figure 124: shoulder rib tests in oblique z-direction with arm

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

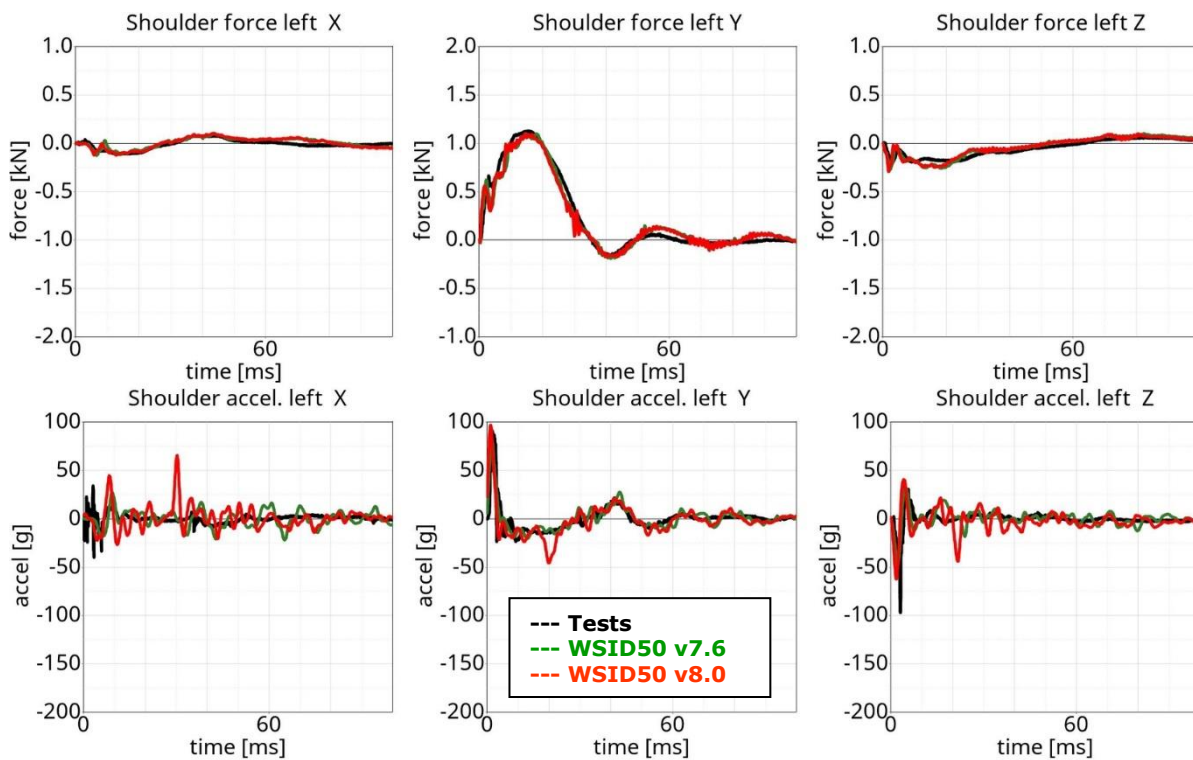


Figure 125: shoulder rib test oblique z-direction with arm – low velocity

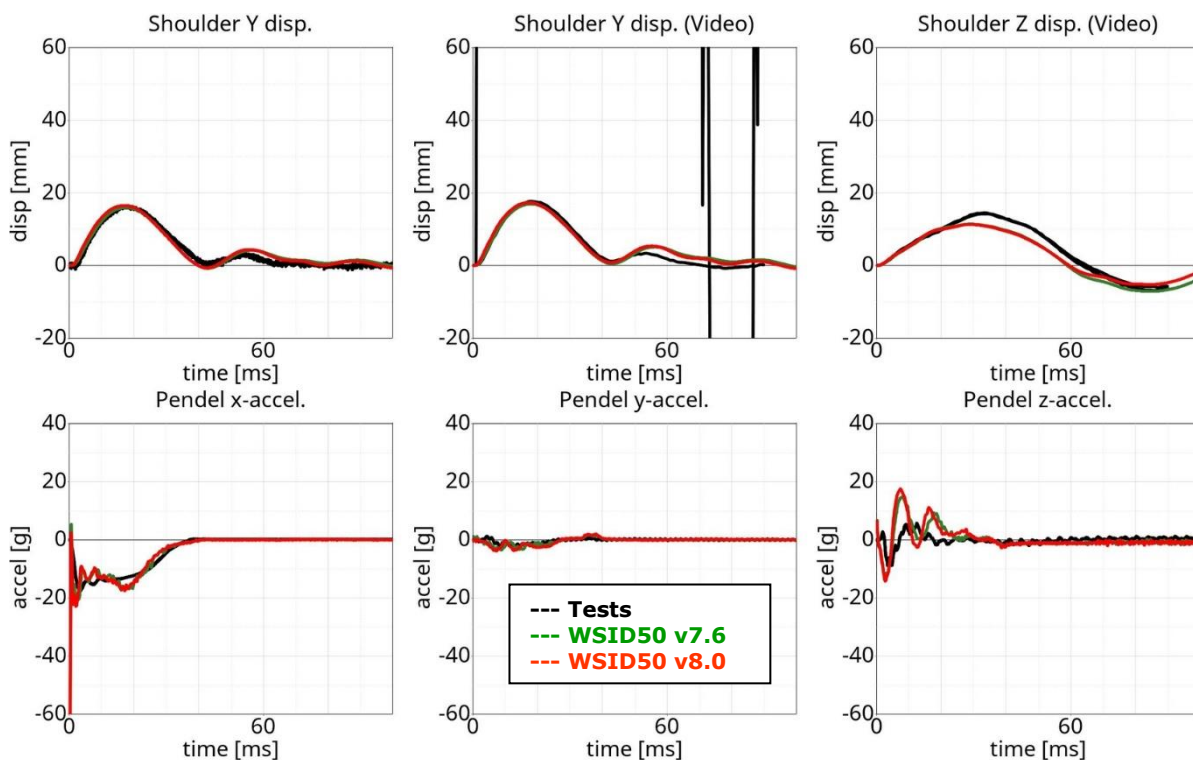


Figure 126: shoulder rib test oblique z-direction – low velocity

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

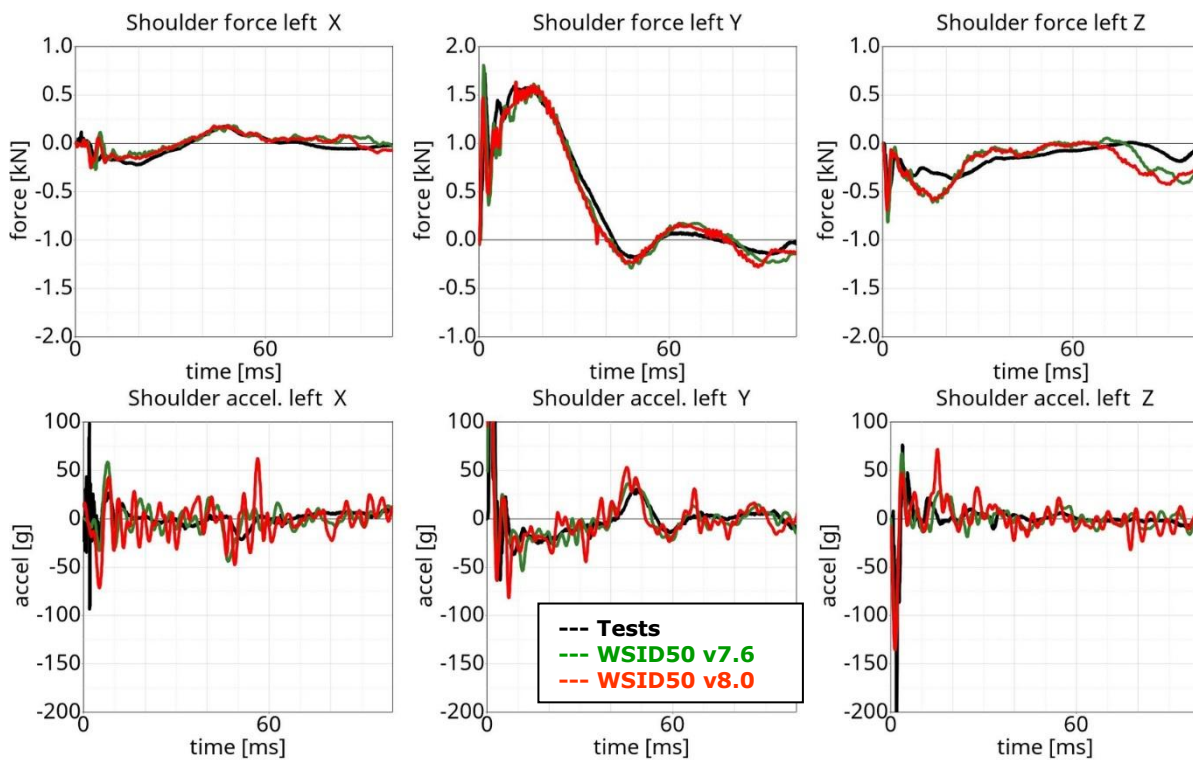


Figure 127: shoulder rib test oblique z-direction with arm – medium velocity

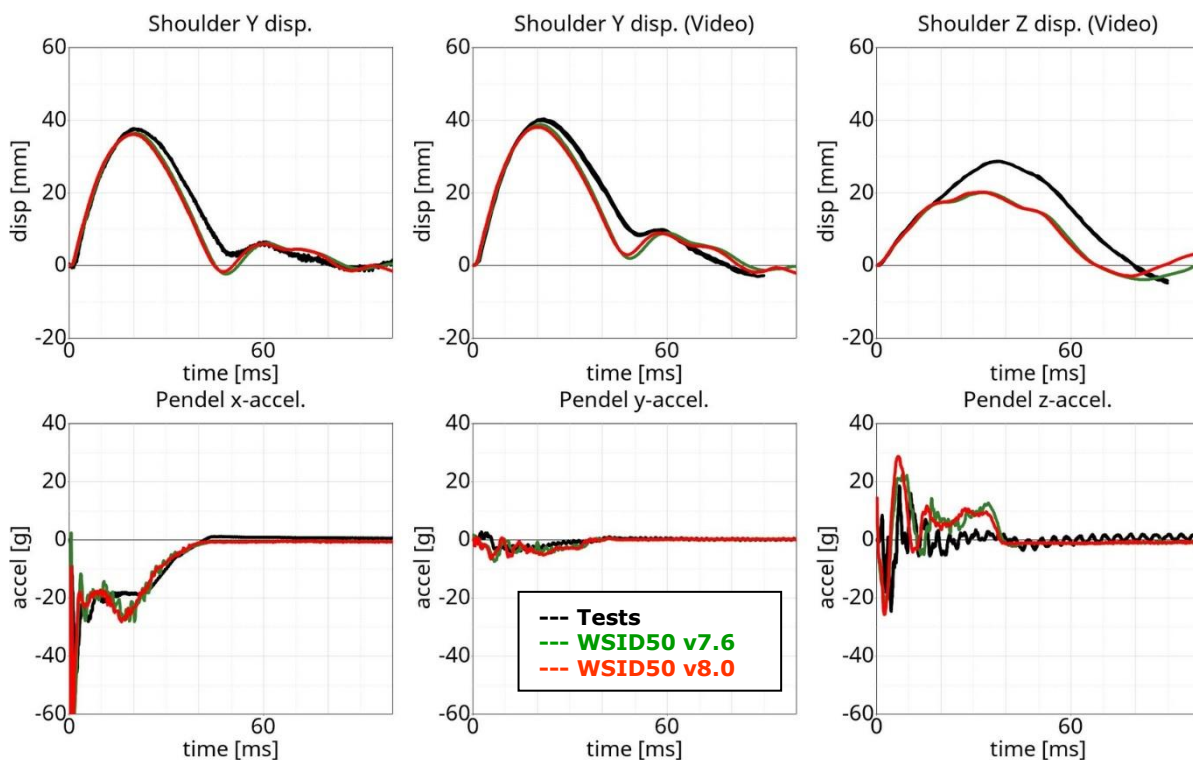


Figure 128: shoulder rib test oblique z-direction – medium velocity

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

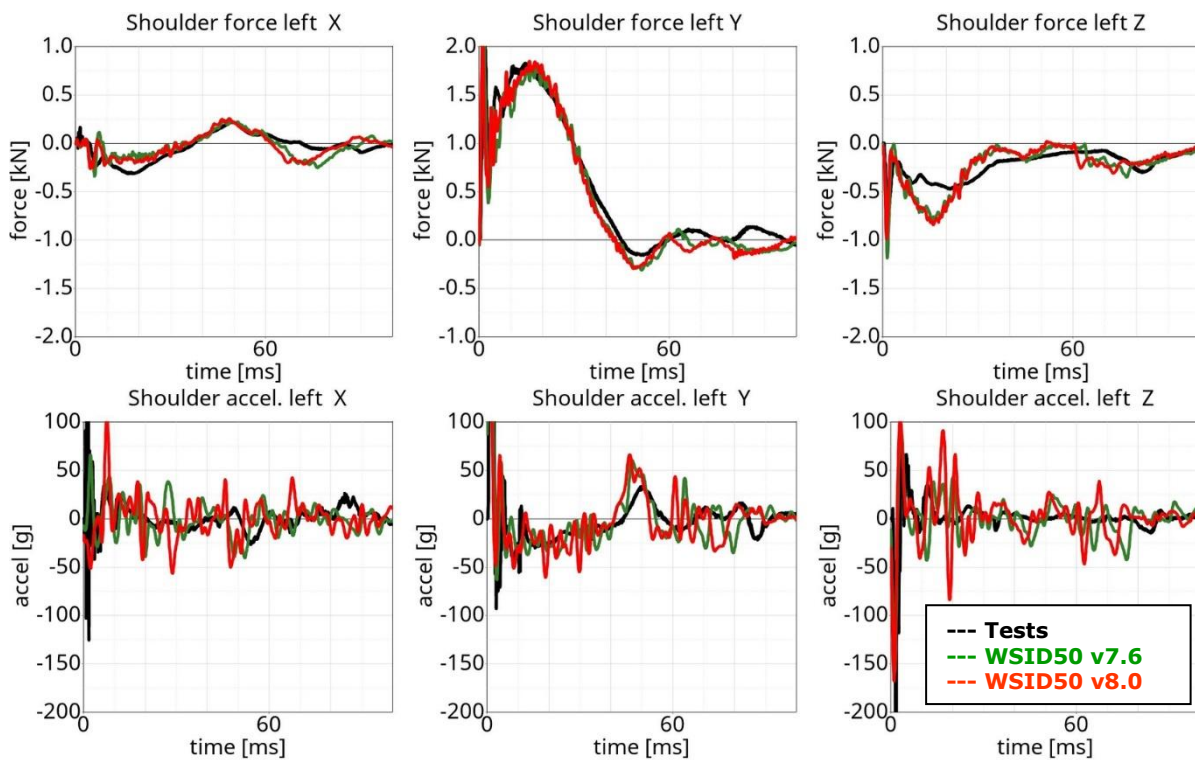


Figure 129: shoulder rib test oblique z-direction with arm – high velocity

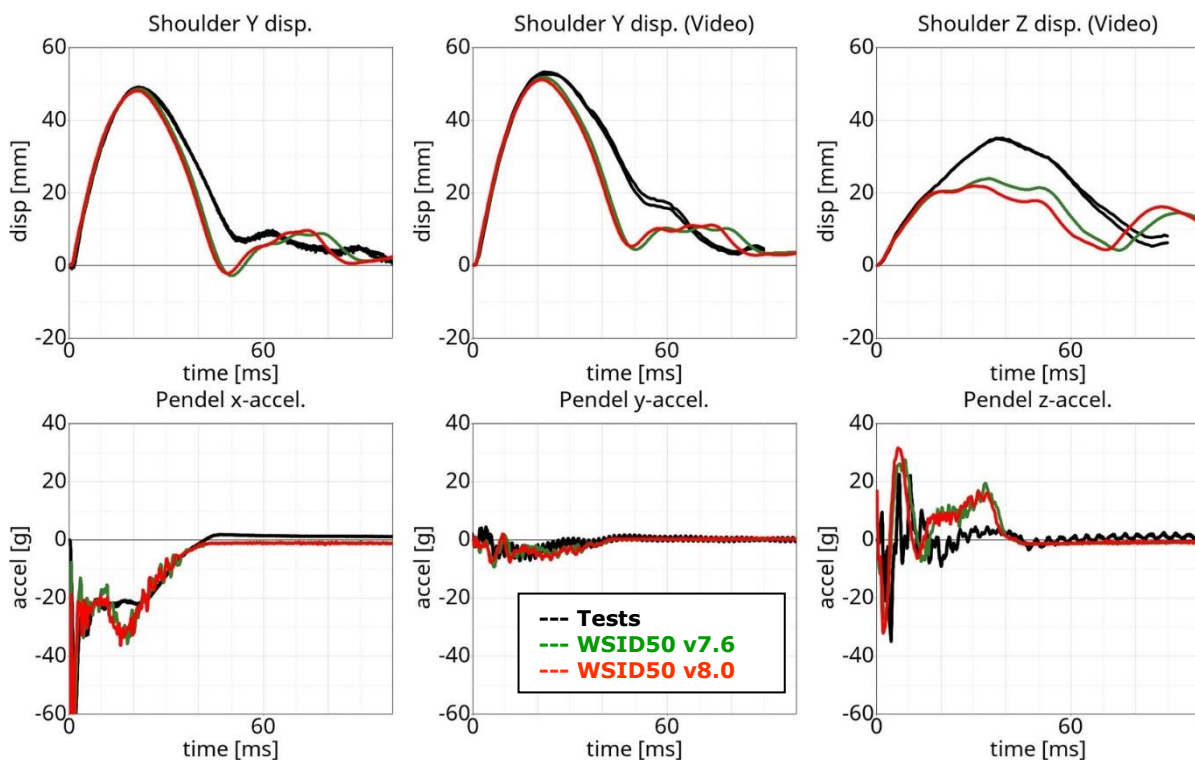


Figure 130: shoulder rib test oblique z-direction – high velocity

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

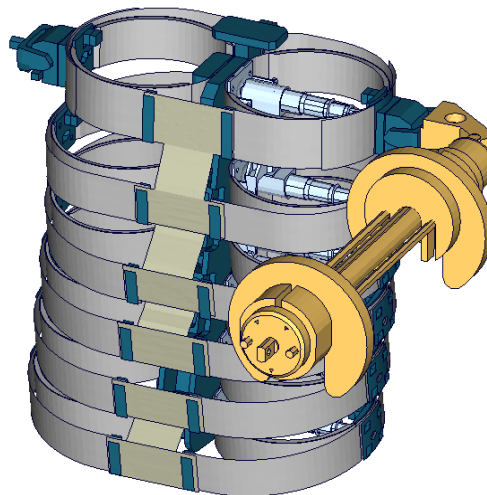


Figure 131: Additional shoulder rib test, 0 degree with sternum

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

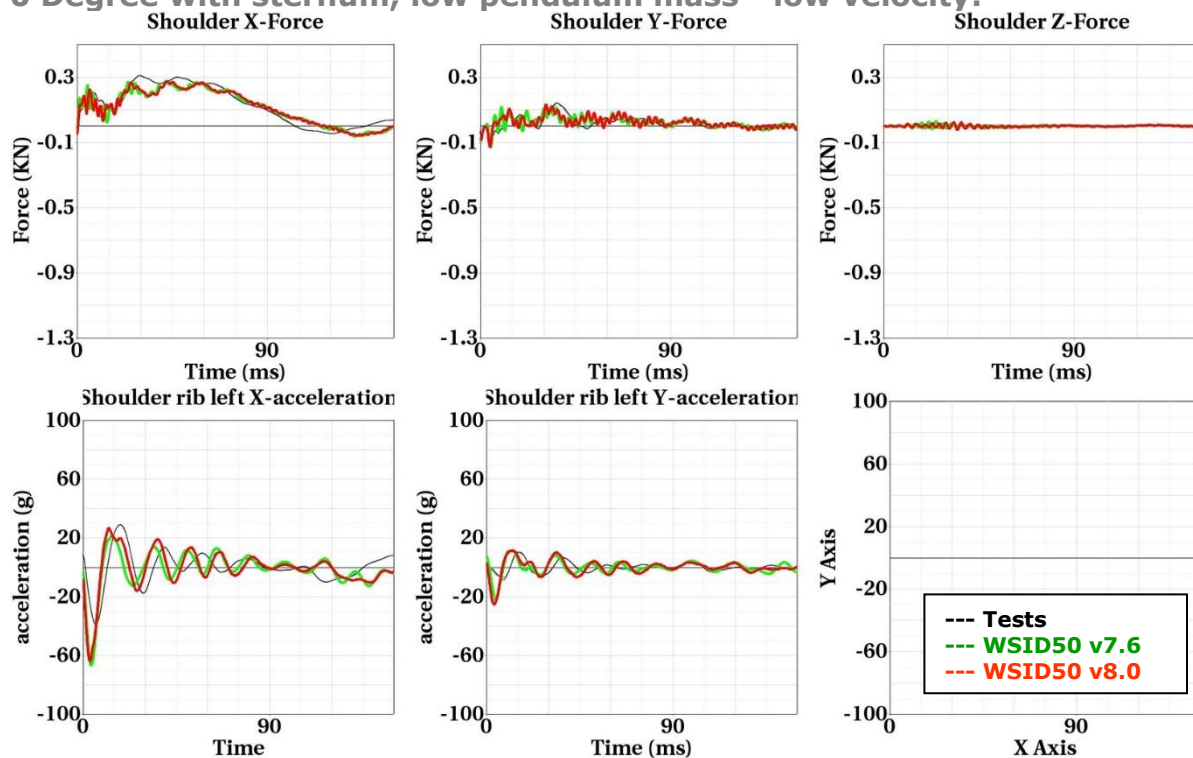


Figure 132: 0 Degree with sternum – low velocity

Performance – component tests

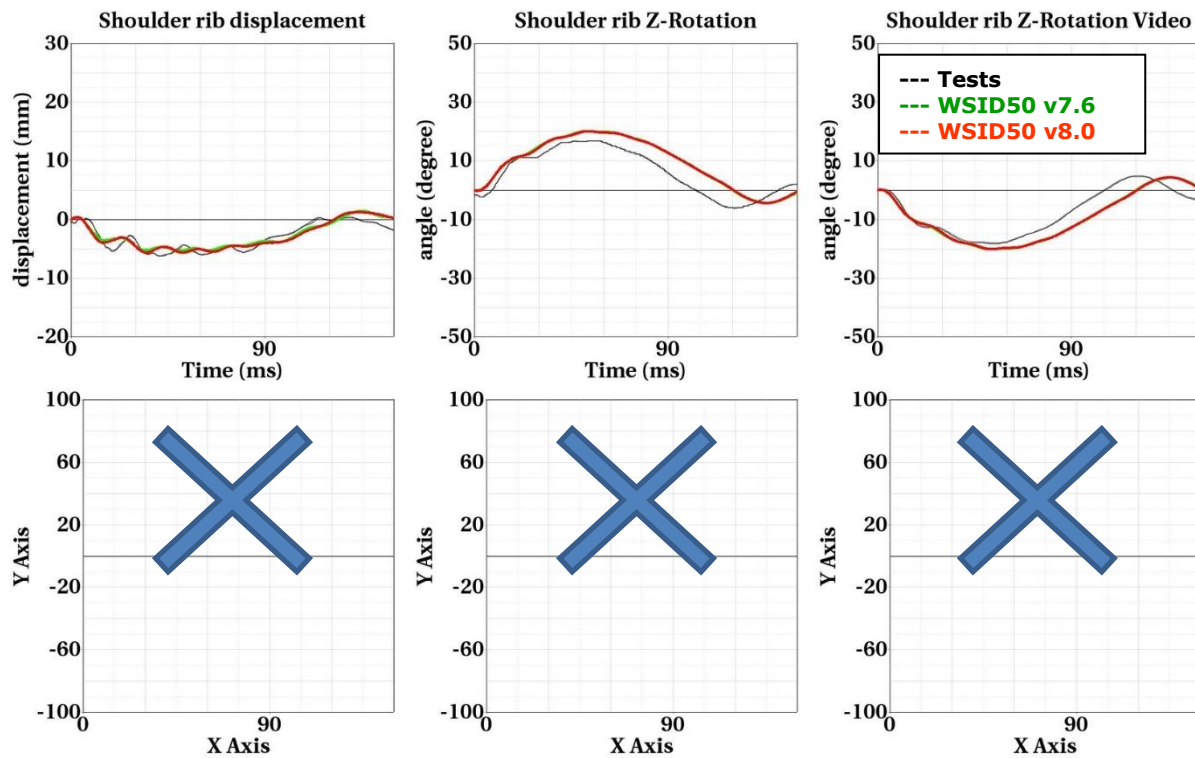


Figure 133: 0 Degree with sternum – low velocity

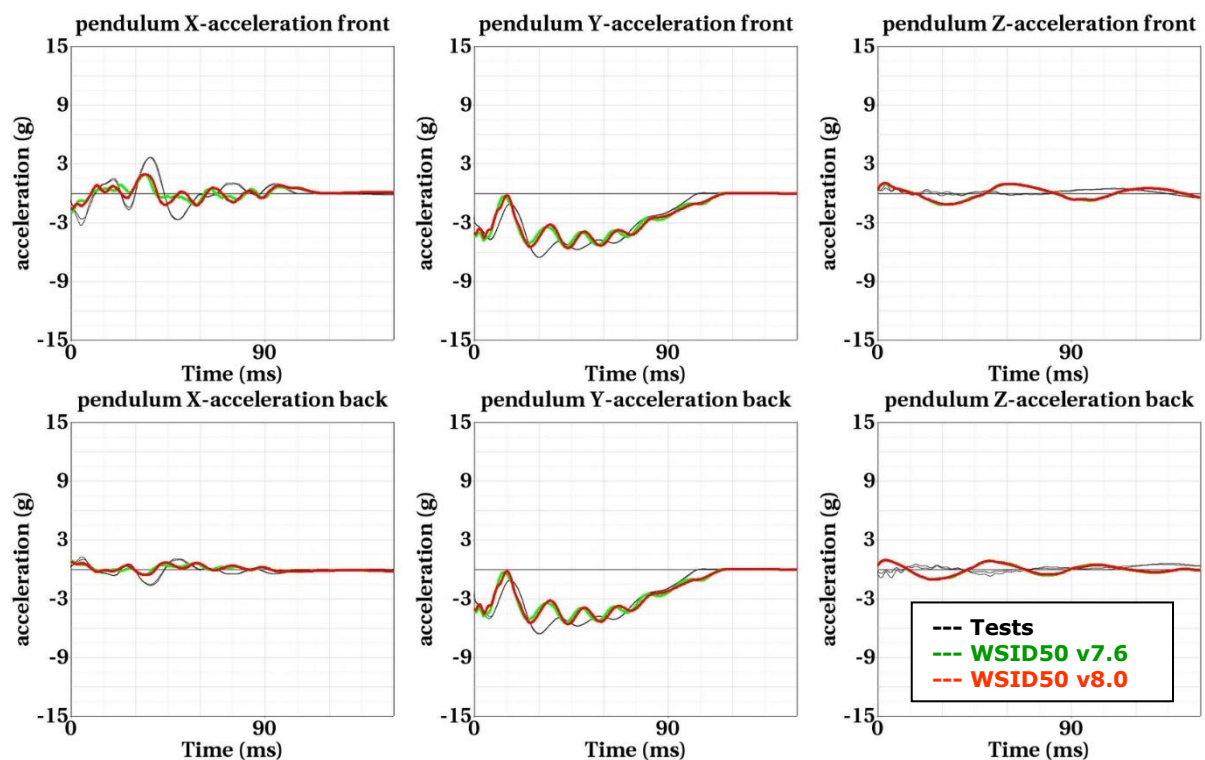


Figure 134: 0 Degree with sternum – low velocity

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

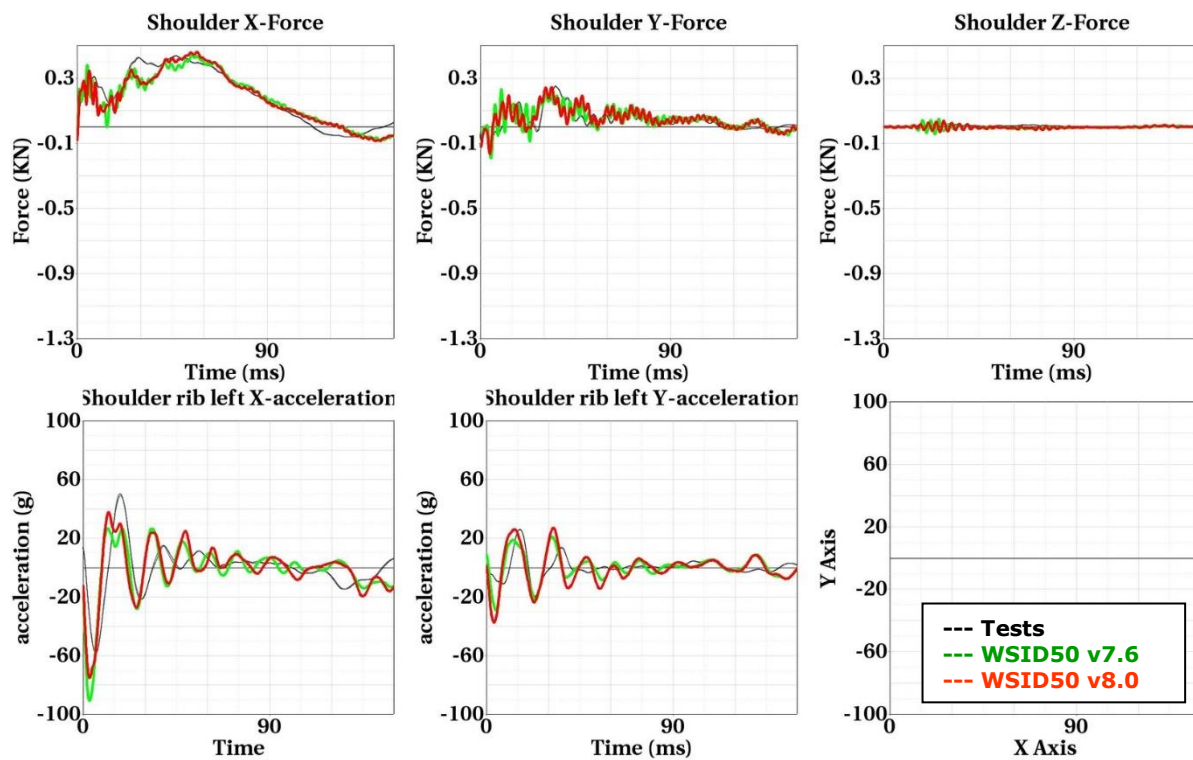


Figure 135: 0 Degree with sternum – high velocity

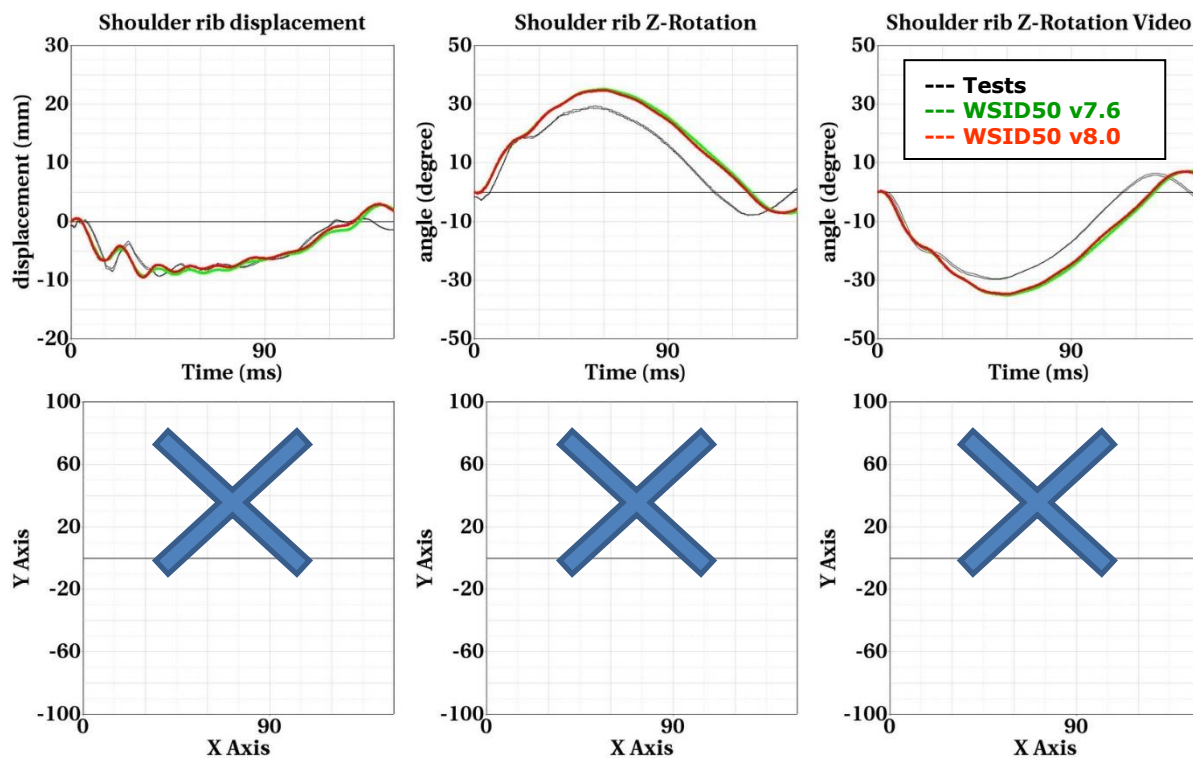


Figure 136: 0 Degree with sternum – high velocity

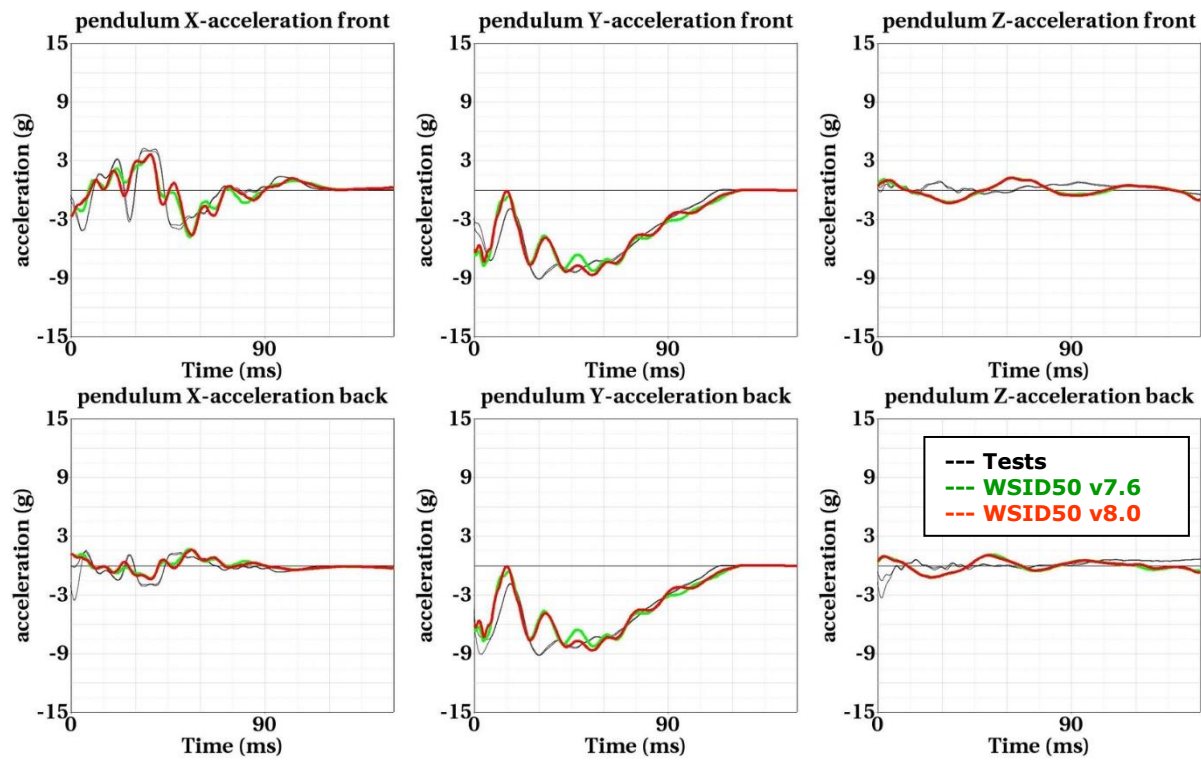


Figure 137: 0 Degree with sternum – high velocity

0 Degree without sternum

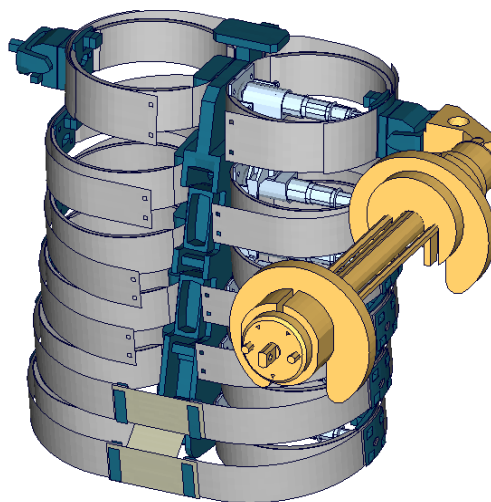


Figure 138: Additional shoulder rib test, 0 degree without sternum

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

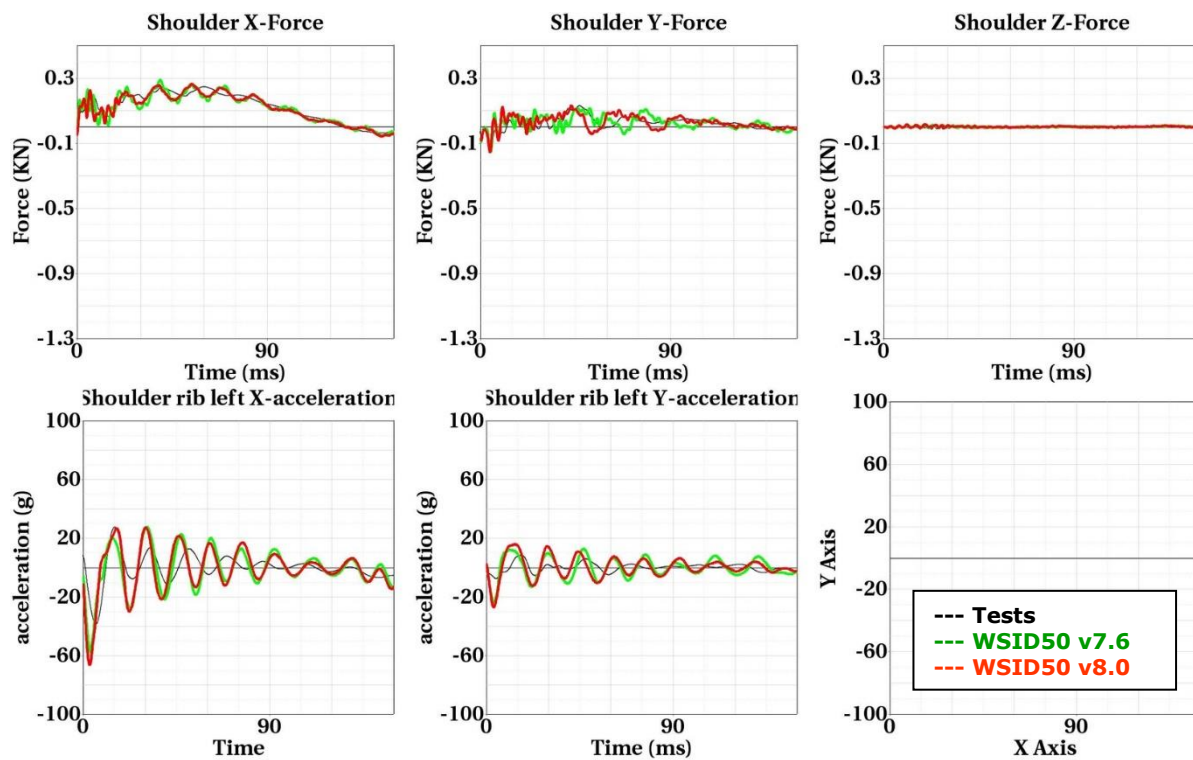


Figure 139: 0 Degree without sternum – low velocity

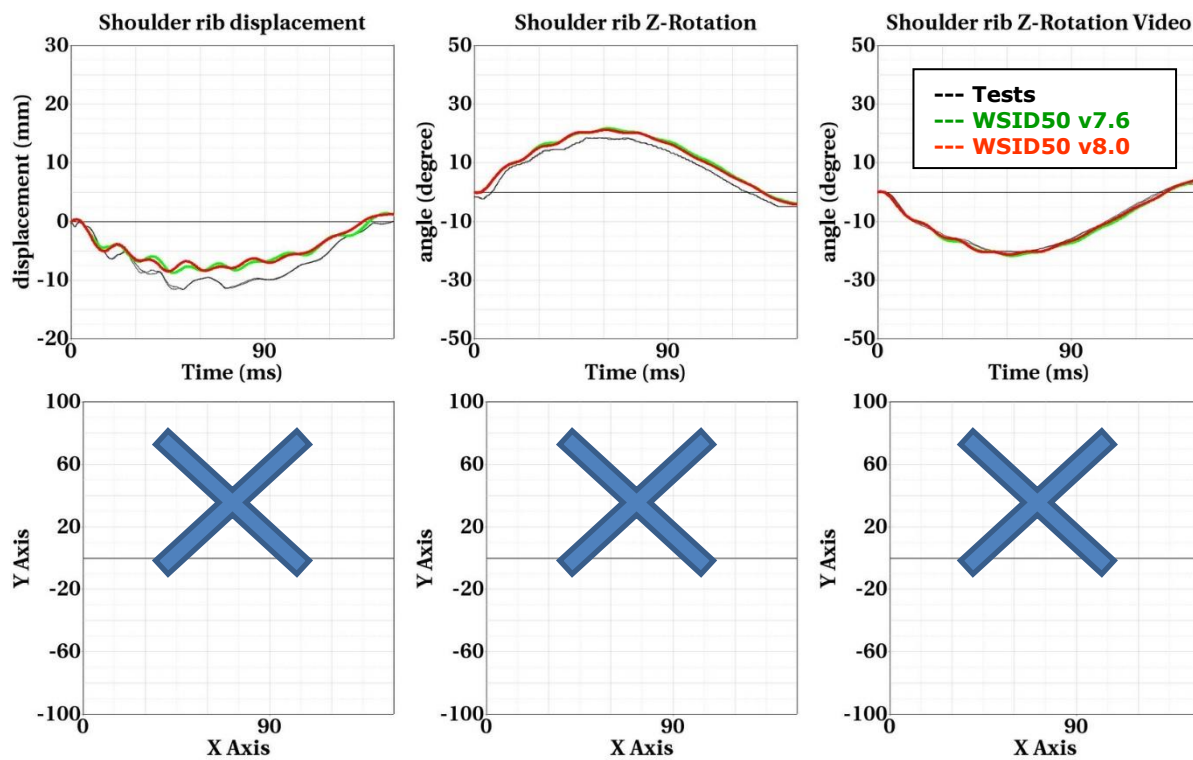


Figure 140: 0 Degree without sternum – low velocity

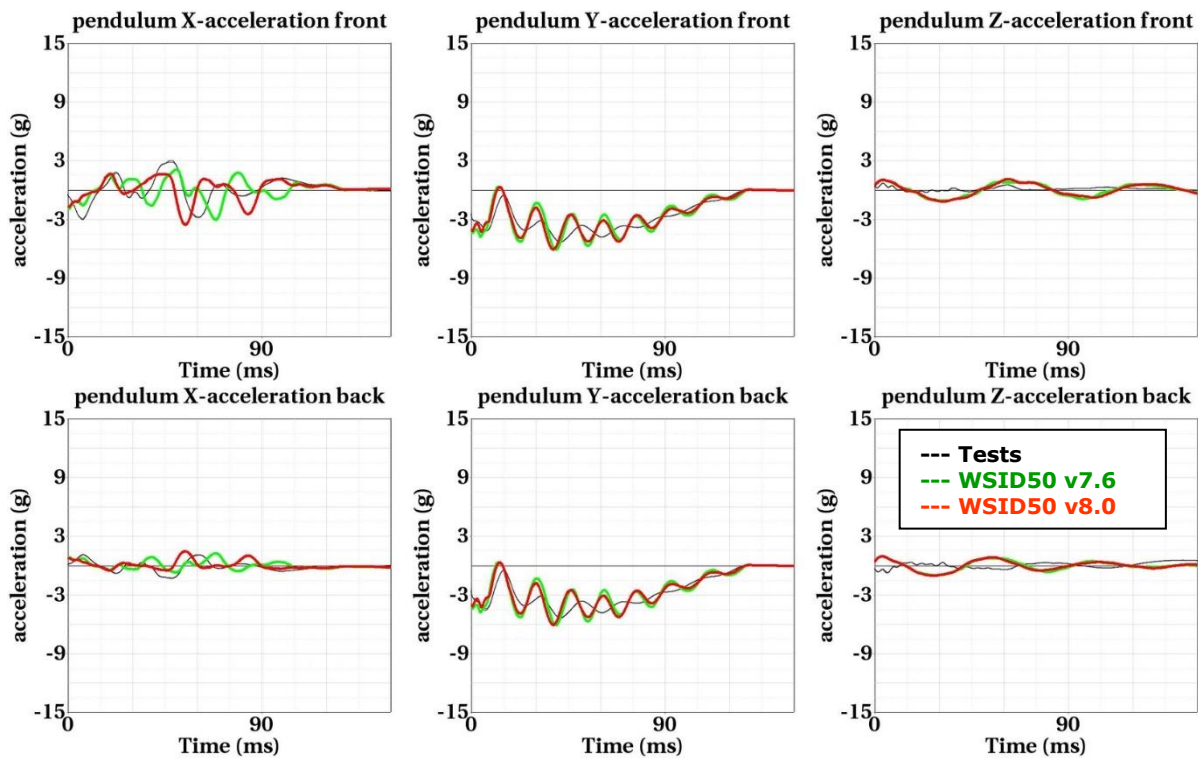


Figure 141: 0 Degree without sternum – low velocity

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

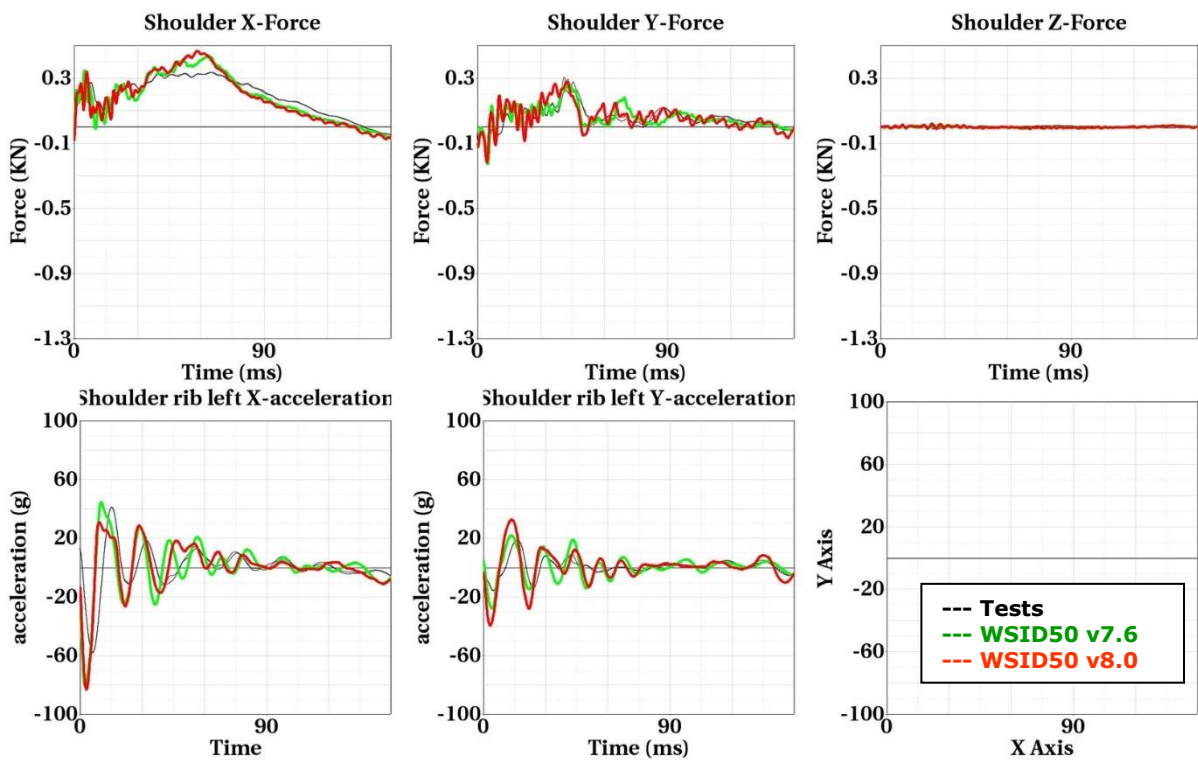


Figure 142: 0 Degree without sternum – high velocity

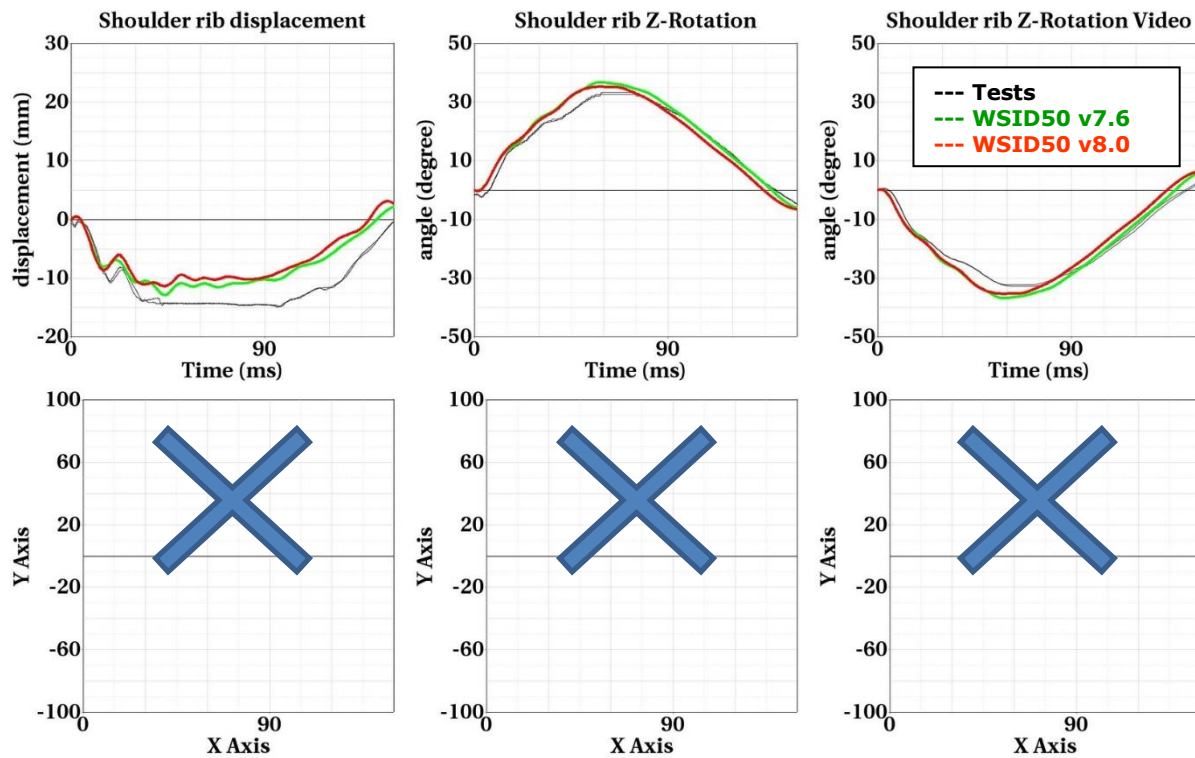


Figure 143: 0 Degree without sternum – high velocity

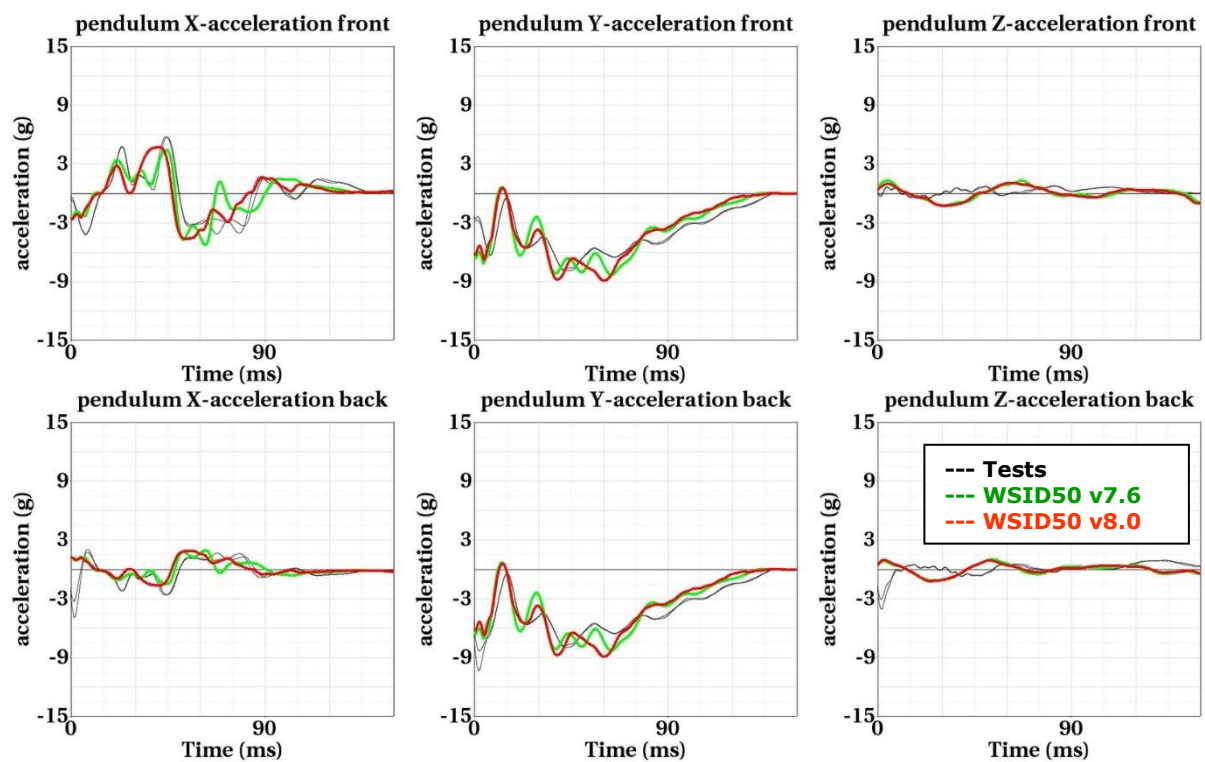


Figure 144: 0 Degree without sternum – high velocity

90 Degree with sternum

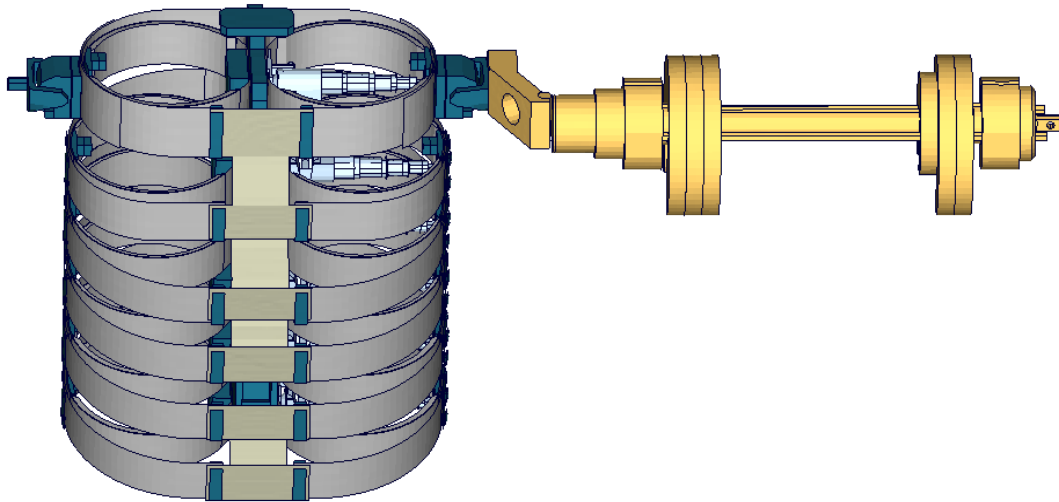


Figure 145: Additional shoulder rib test, 90 degree with sternum

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

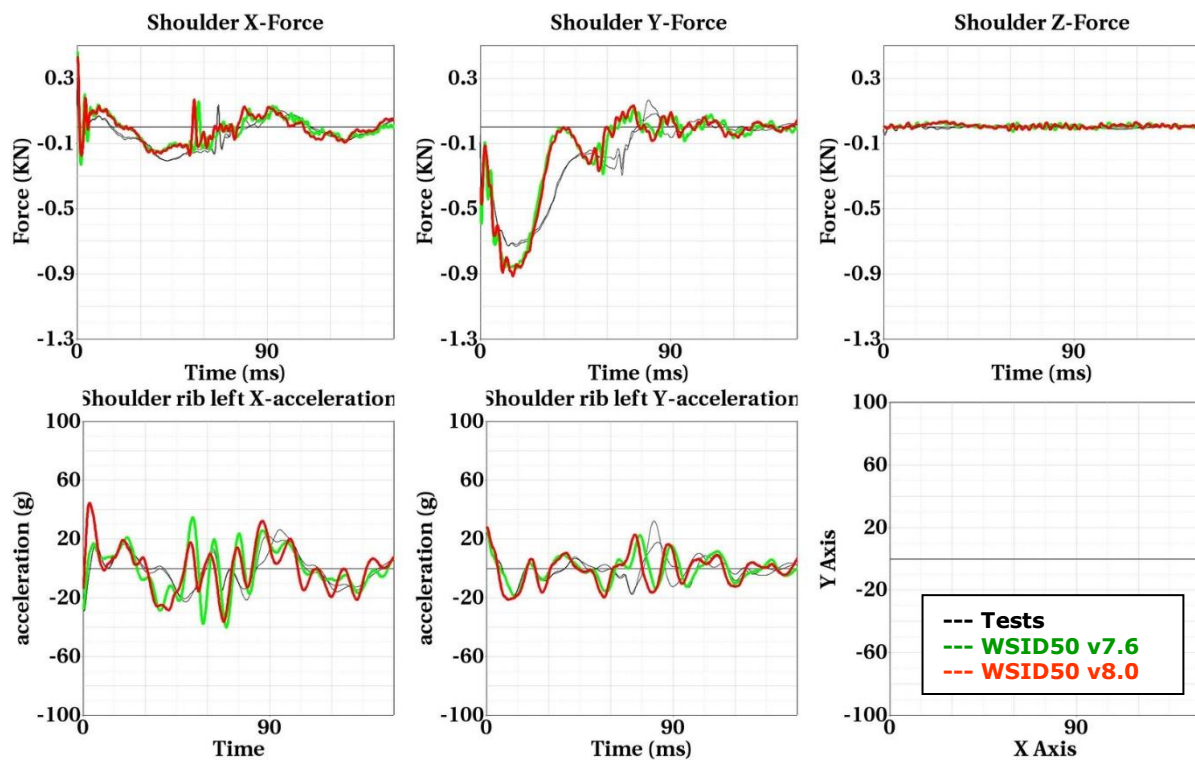


Figure 146: 90 Degree with sternum – low velocity

Performance – component tests

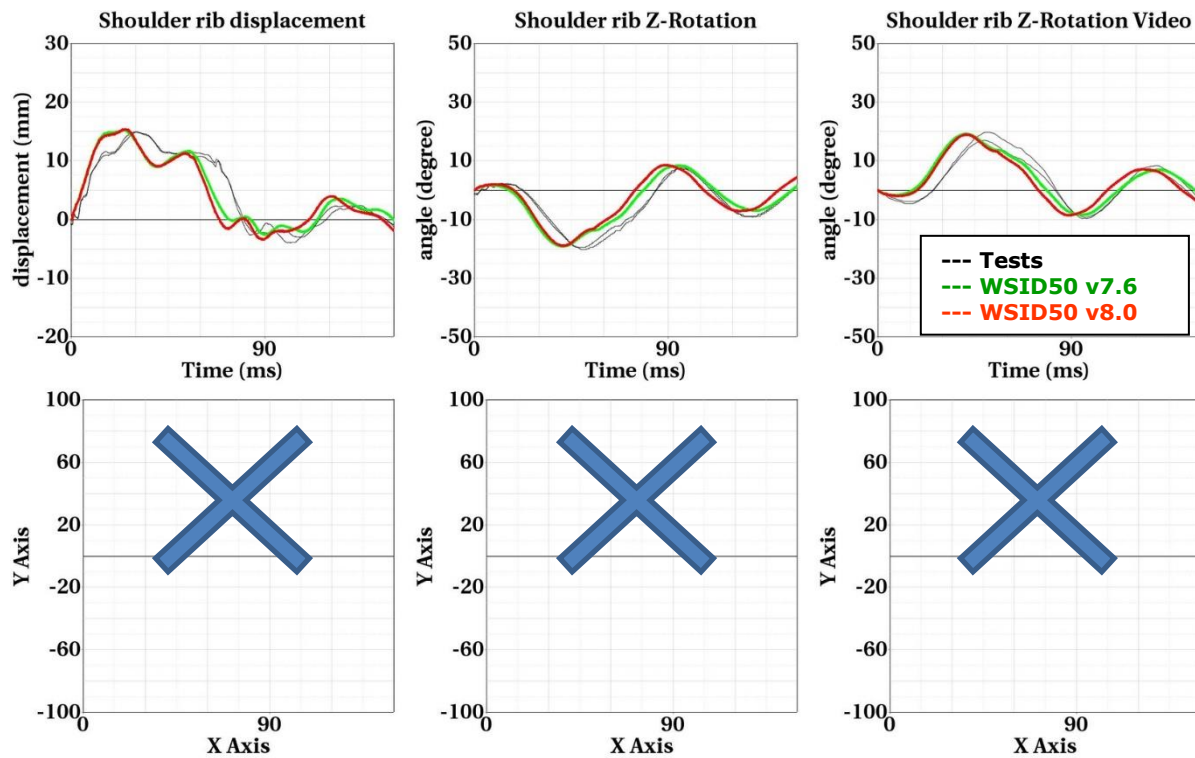


Figure 147: 90 Degree with sternum – low velocity

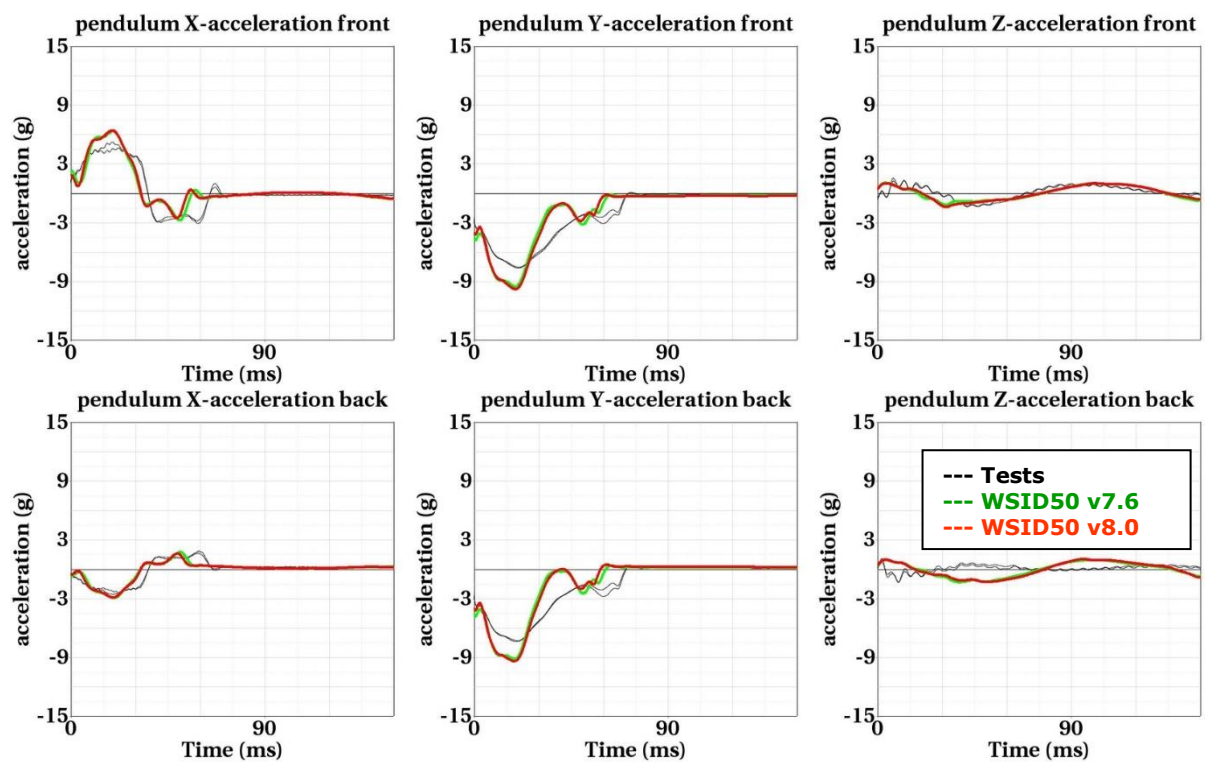


Figure 148: 90 Degree with sternum – low velocity

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

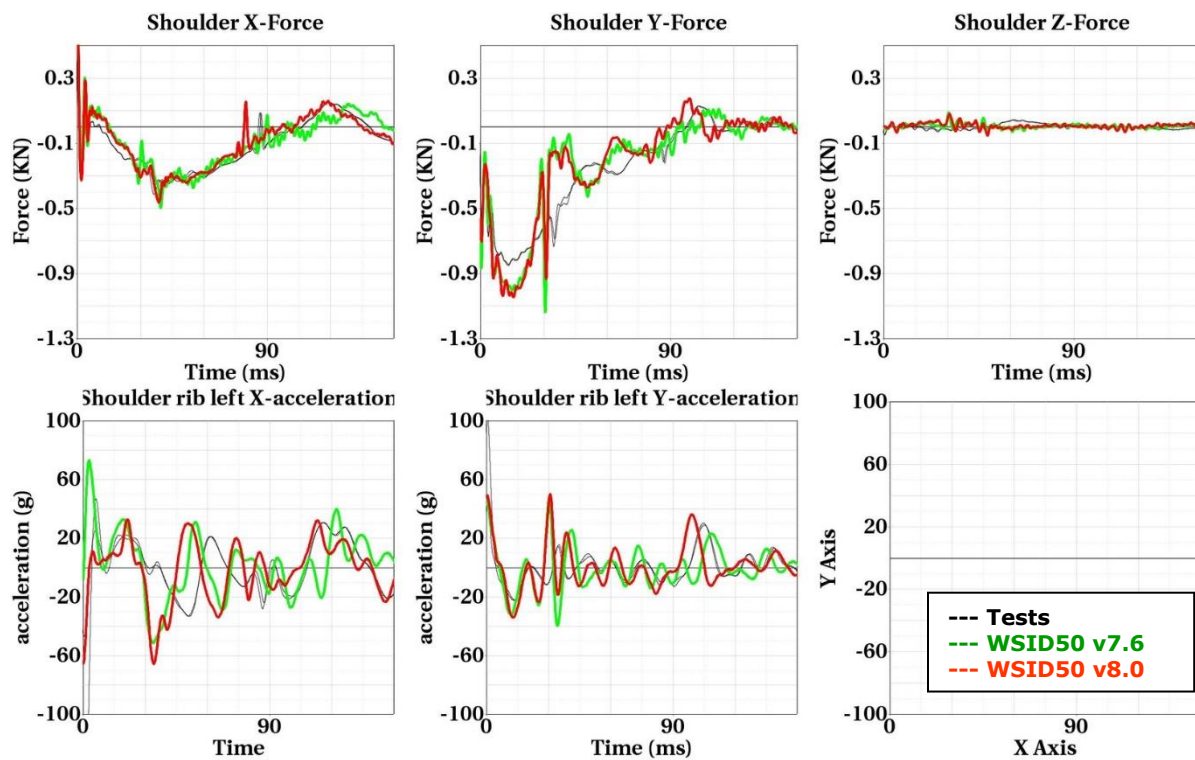


Figure 149: 90 Degree with sternum – high velocity

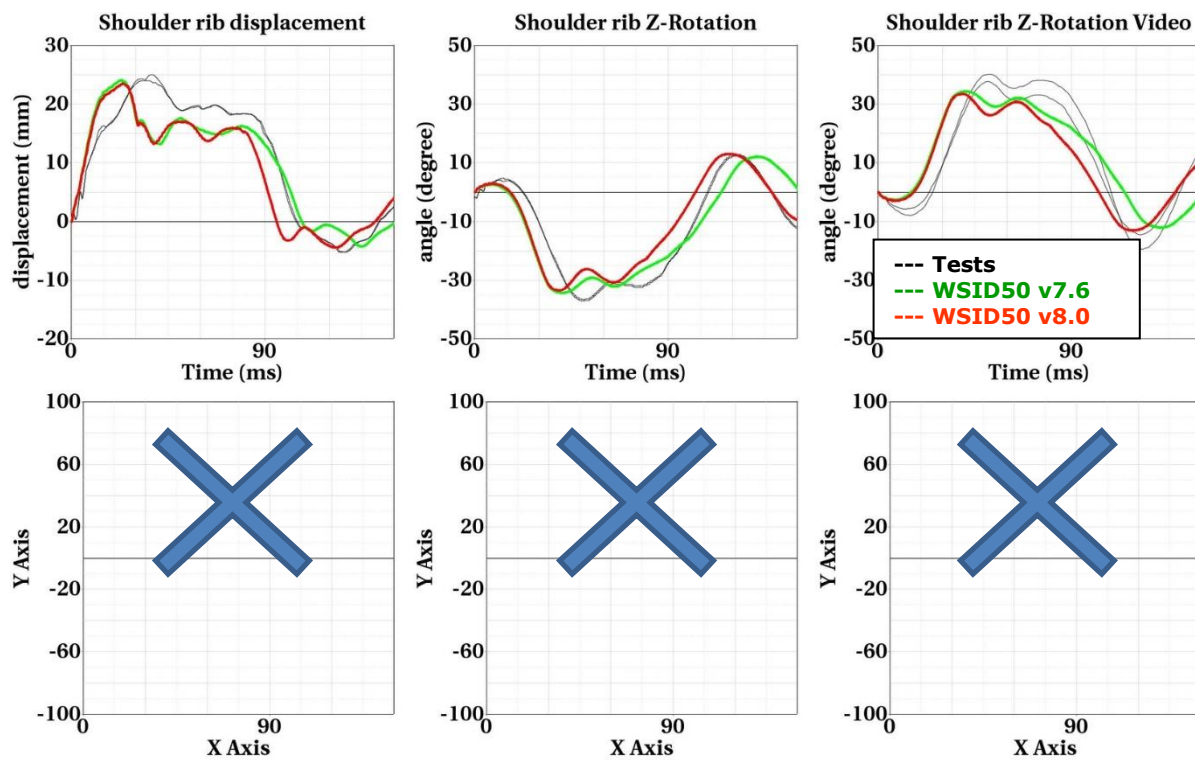


Figure 150: 90 Degree with sternum – high velocity

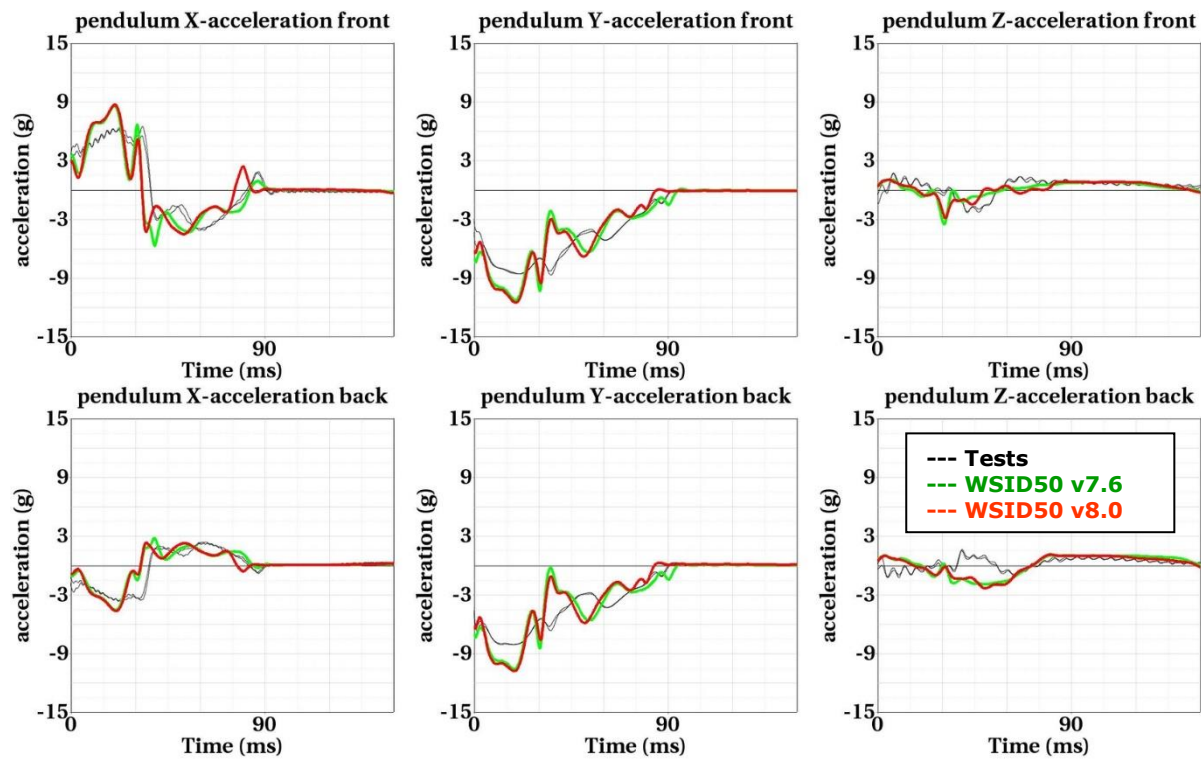


Figure 151: 90 Degree with sternum – high velocity

90 Degree without sternum

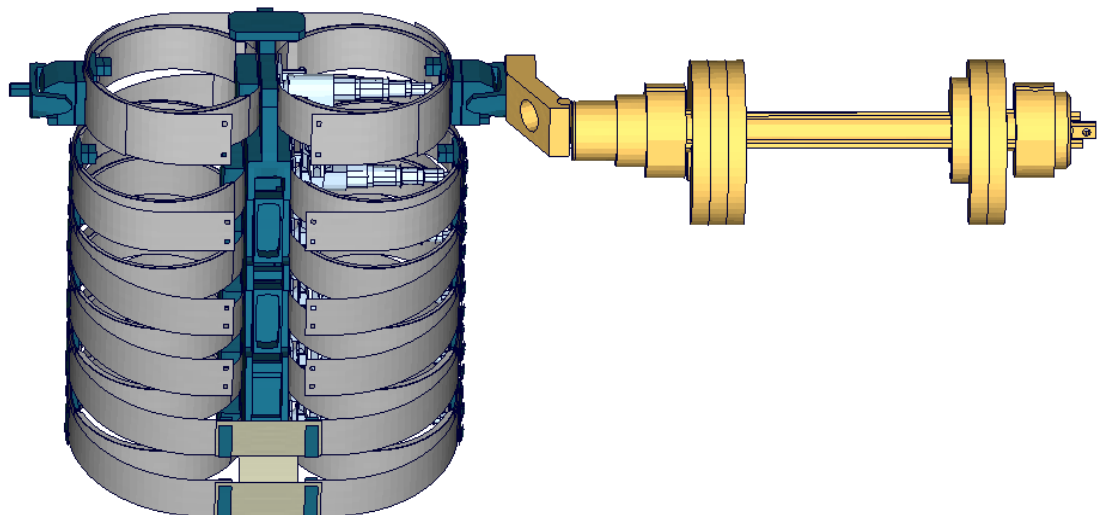


Figure 152: Additional shoulder rib test, 90 degree without sternum

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

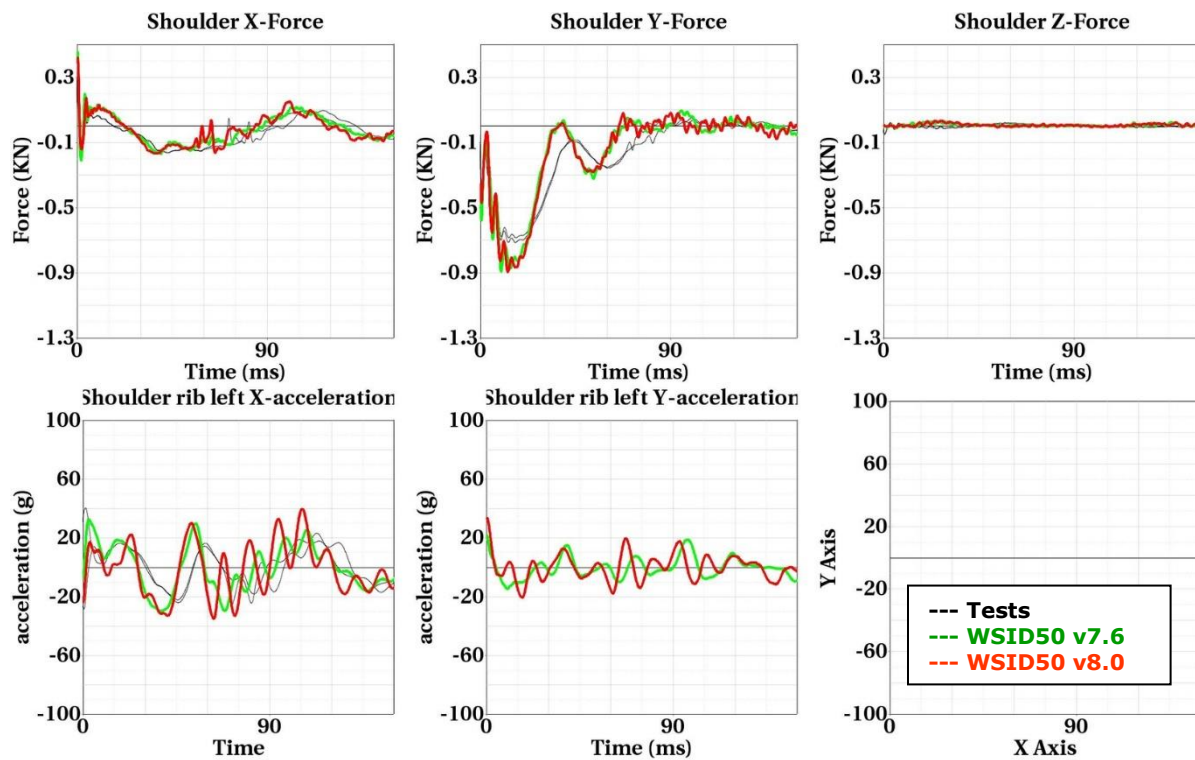


Figure 153: 90 Degree without sternum – low velocity

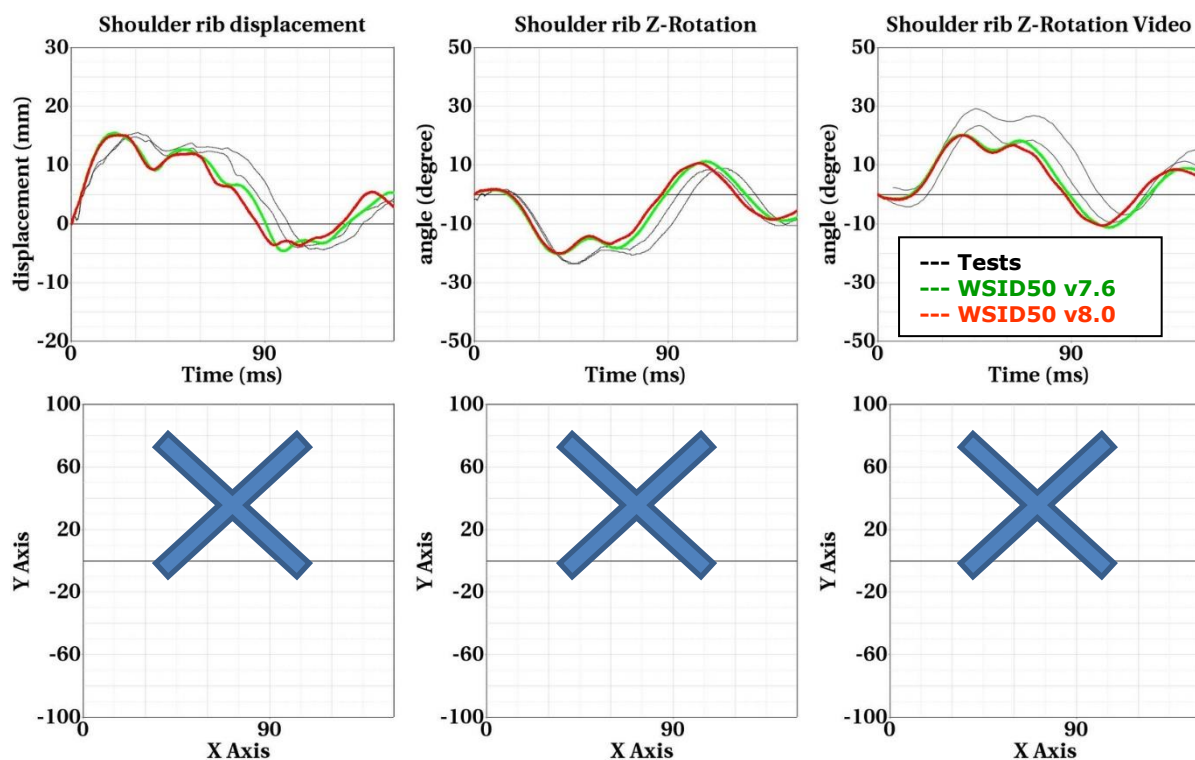


Figure 154: 90 Degree without sternum – low velocity

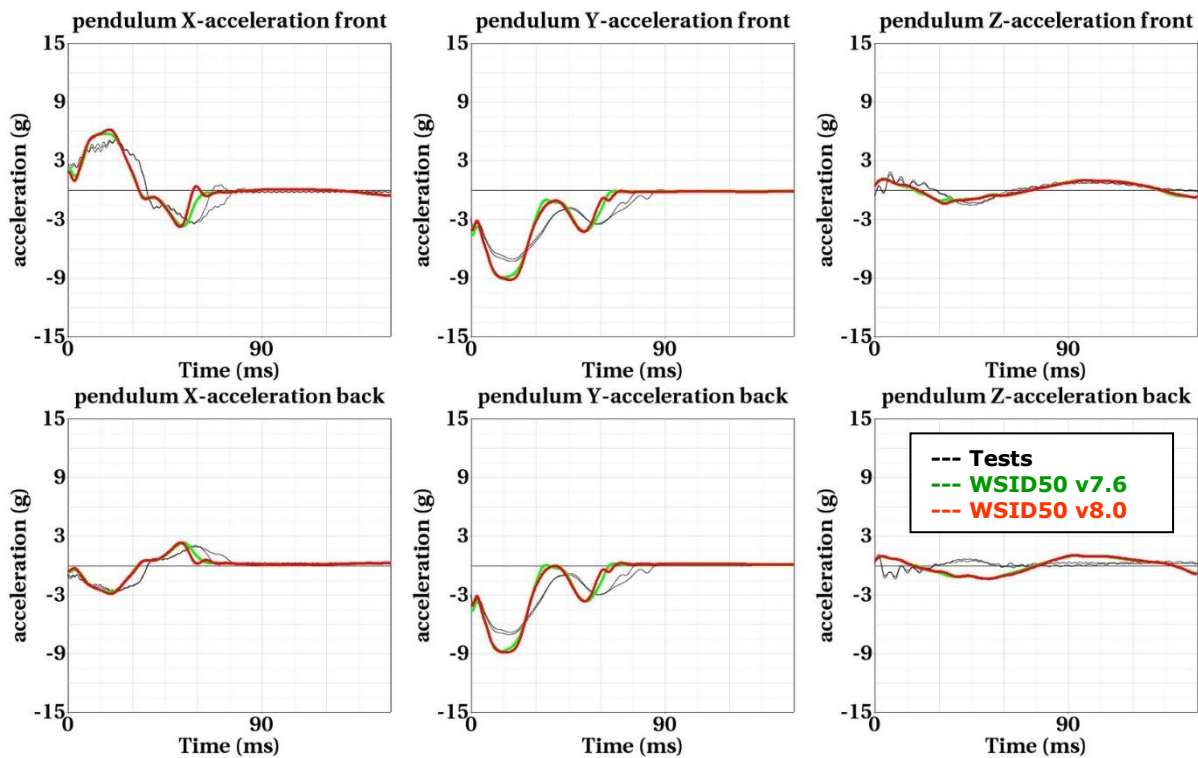


Figure 155: 90 Degree without sternum – low velocity

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

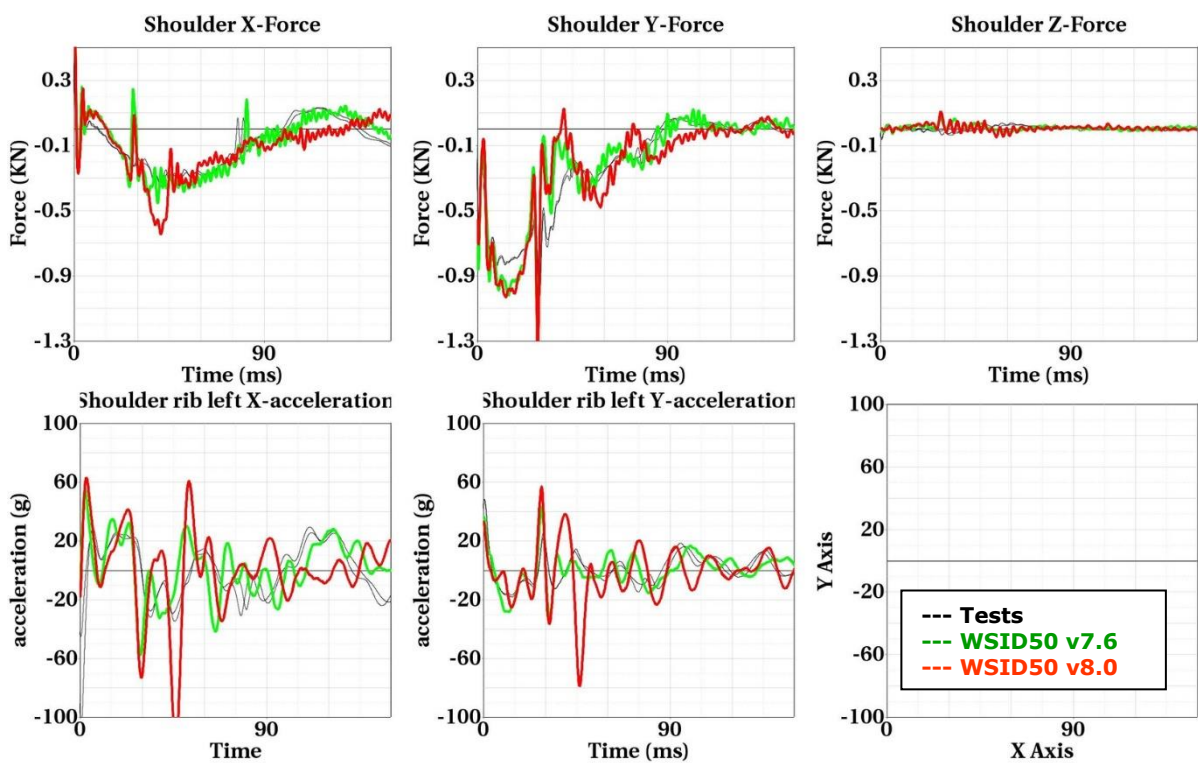


Figure 156: 90 Degree without sternum – high velocity

Performance – component tests

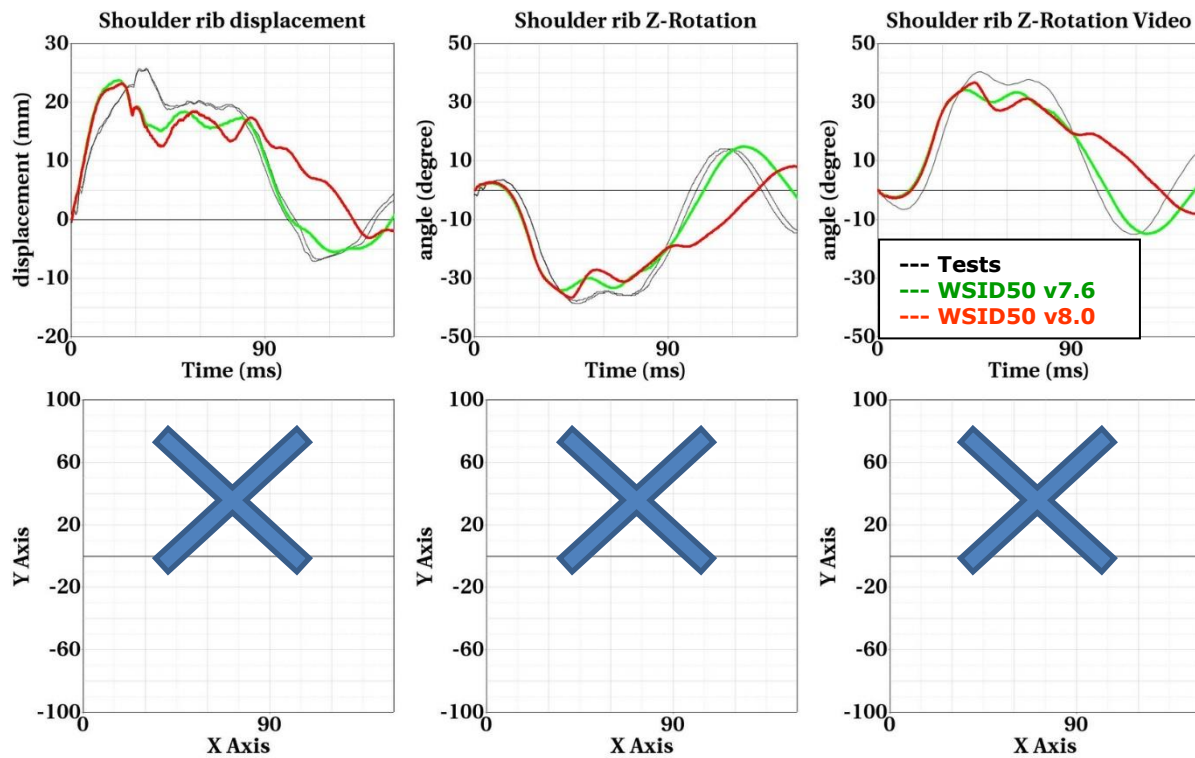


Figure 157: 90 Degree without sternum – high velocity

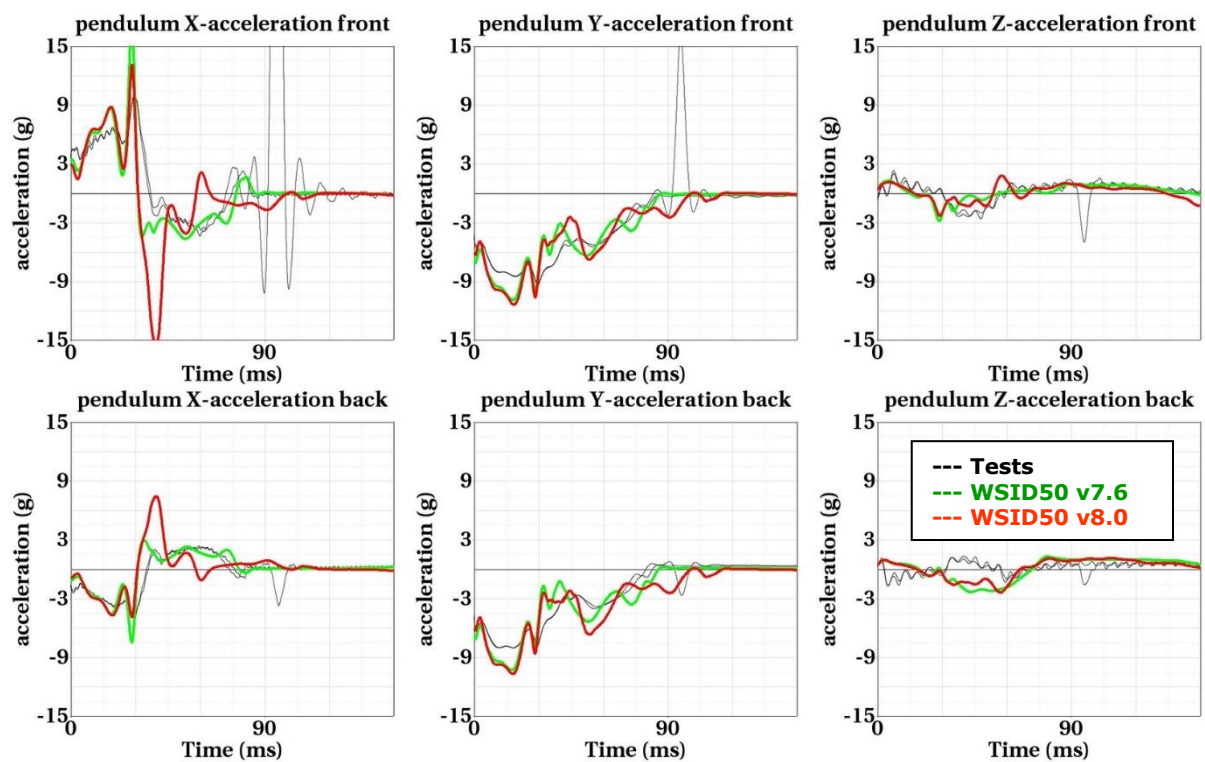


Figure 158: 90 Degree without sternum – high velocity

180 Degree with sternum

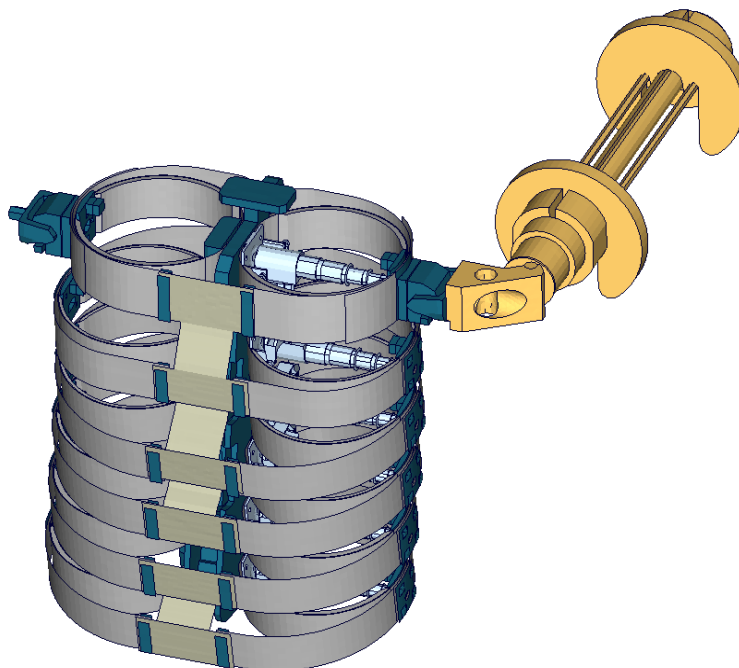


Figure 159: Additional shoulder rib test, 180 degree with sternum

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

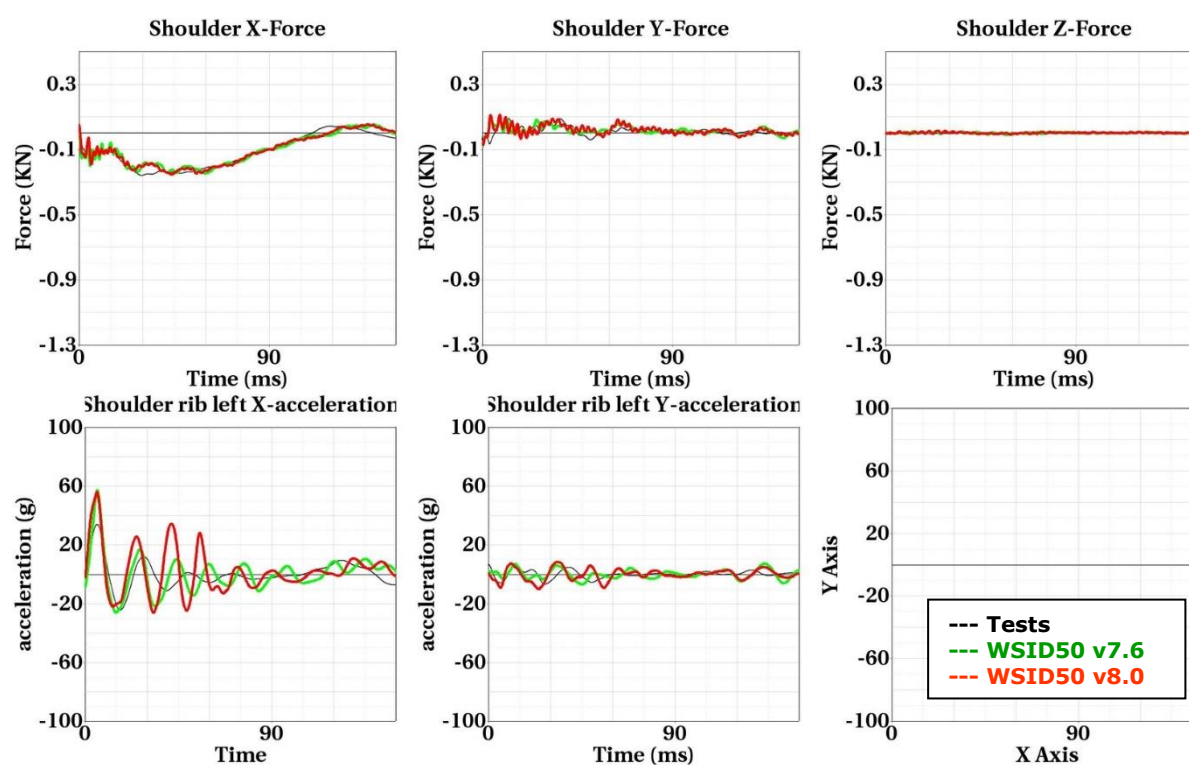


Figure 160: 180 Degree with sternum – low velocity

Performance – component tests

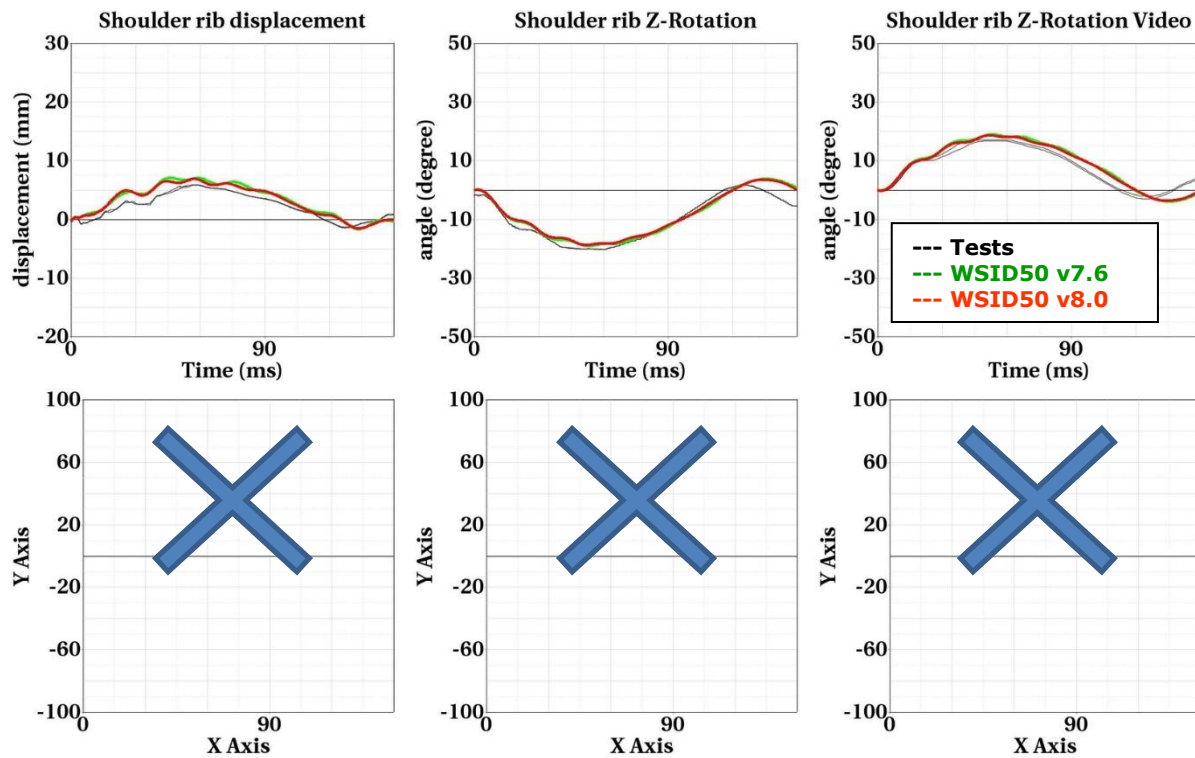


Figure 161: 180 Degree with sternum – low velocity

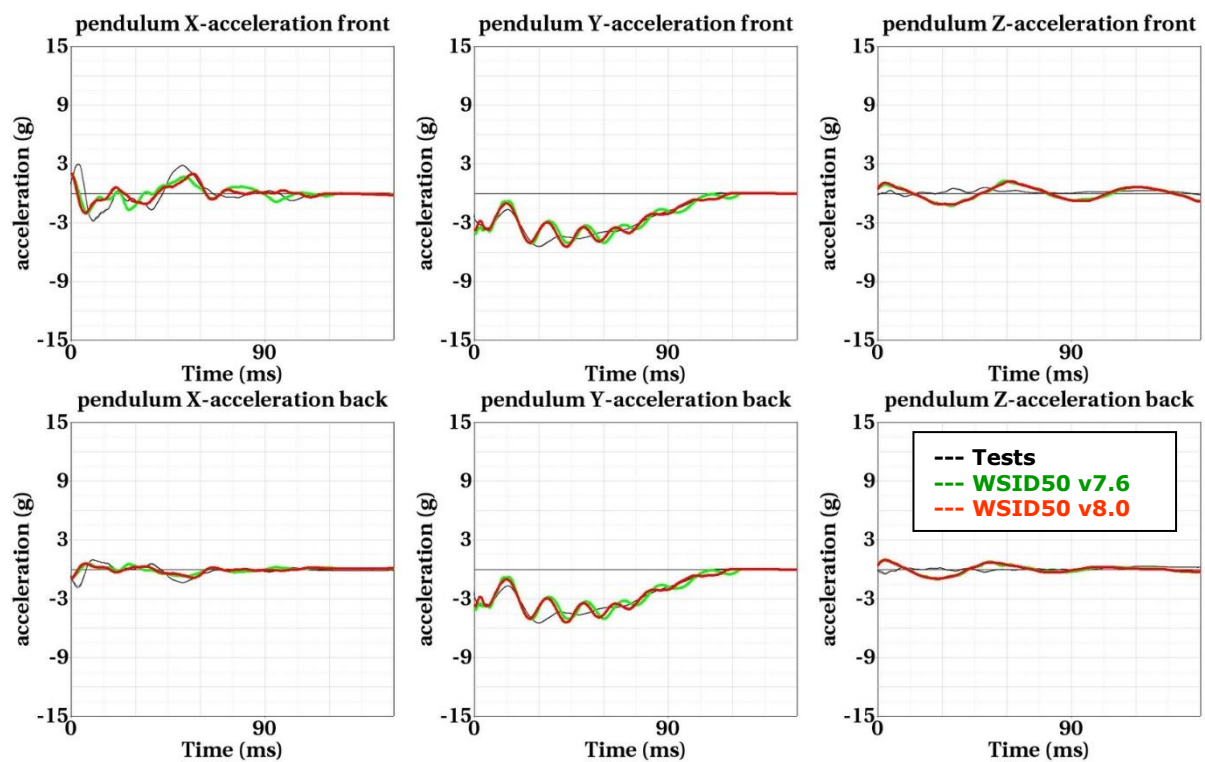


Figure 162: 180 Degree with sternum – low velocity

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

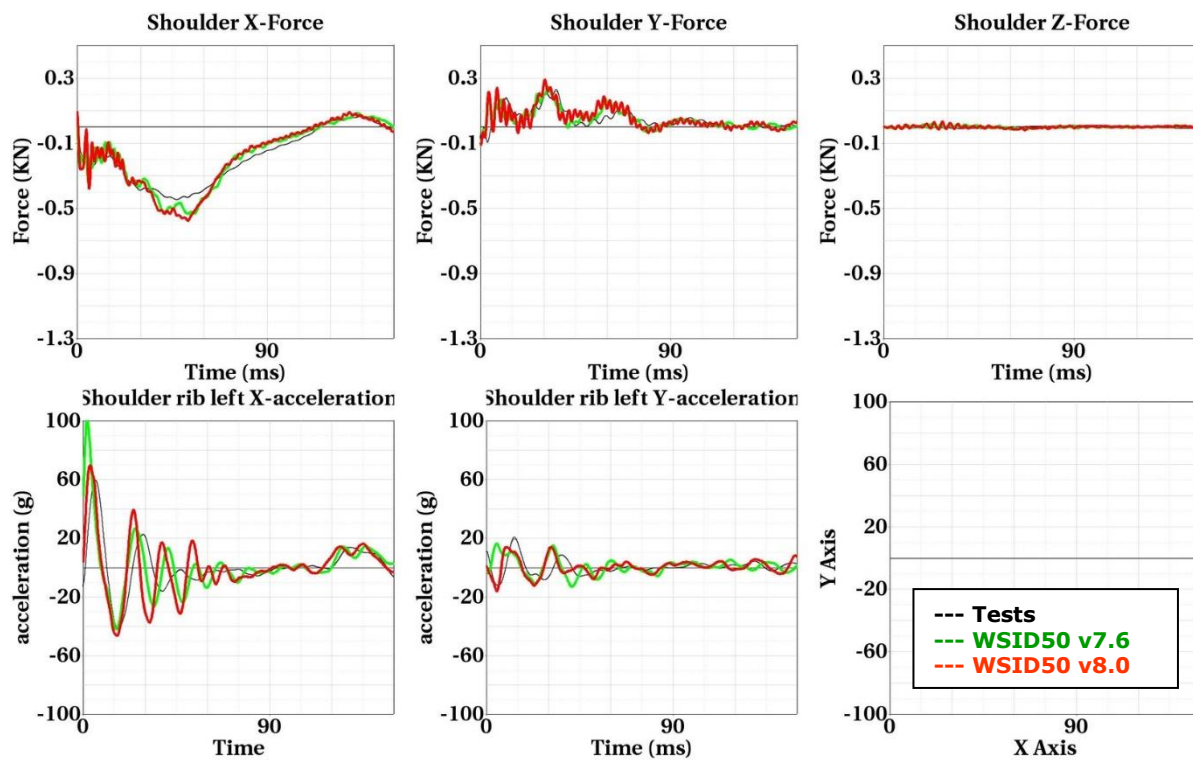


Figure 163: 180 Degree with sternum – high velocity

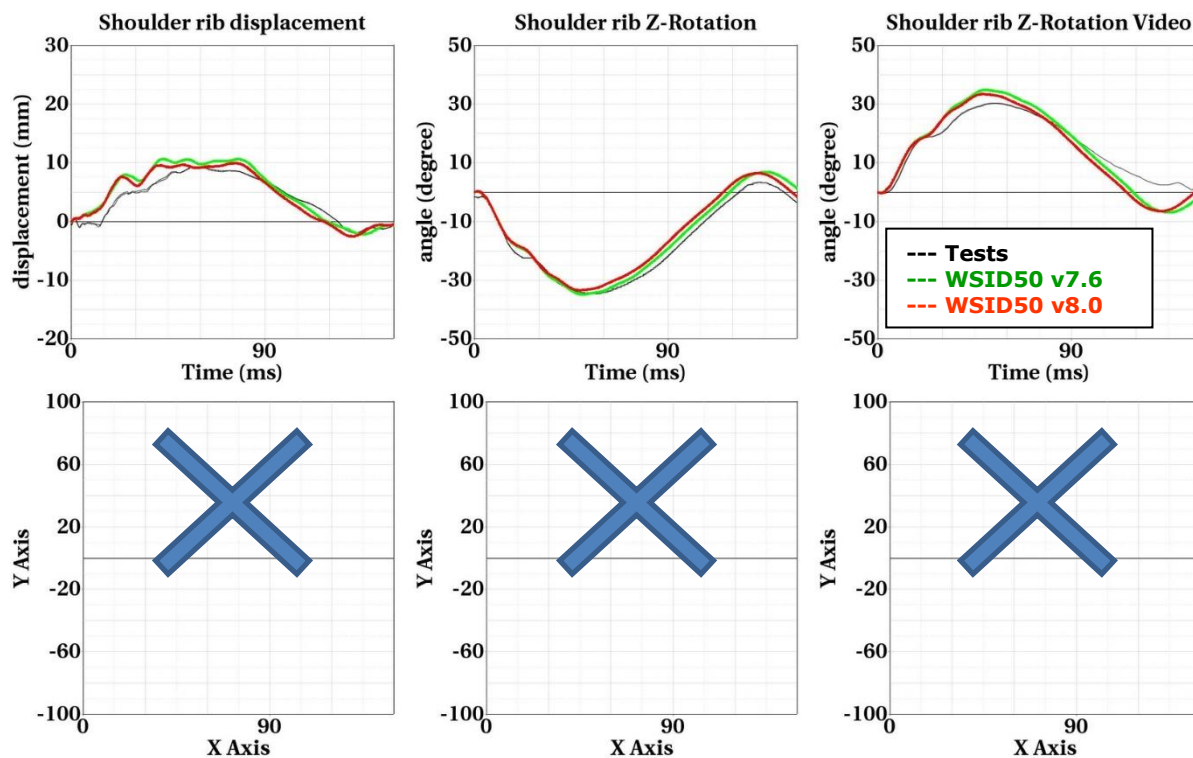


Figure 164: 180 Degree with sternum – high velocity

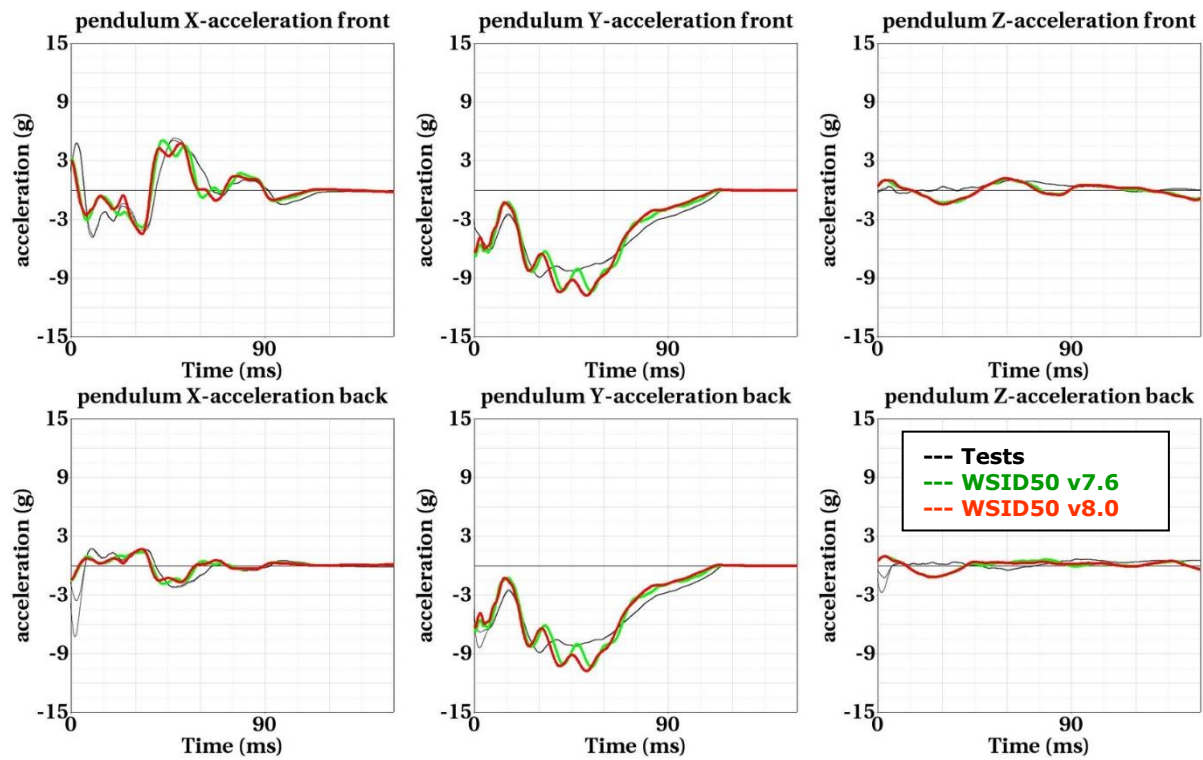


Figure 165: 180 Degree with sternum – high velocity

180 Degree without sternum

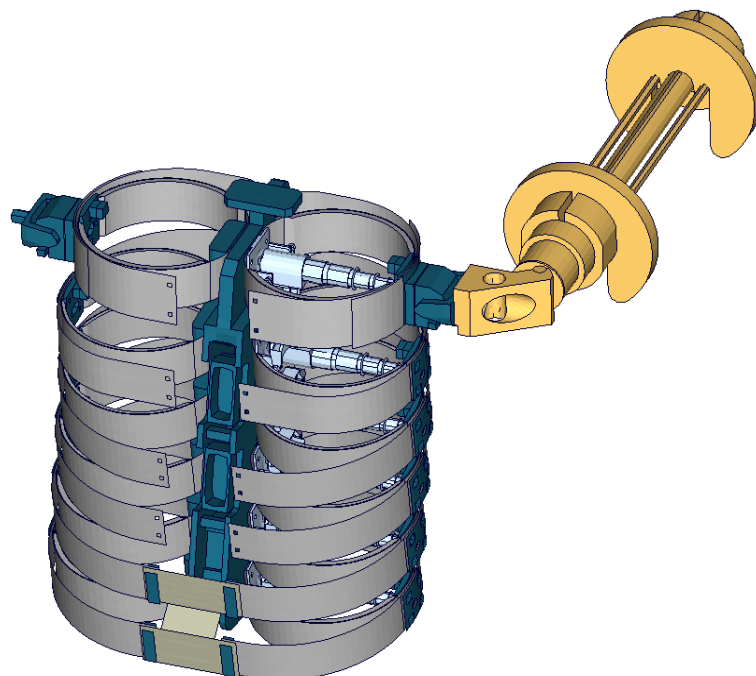


Figure 166: Additional shoulder rib test, 180 degree without sternum

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

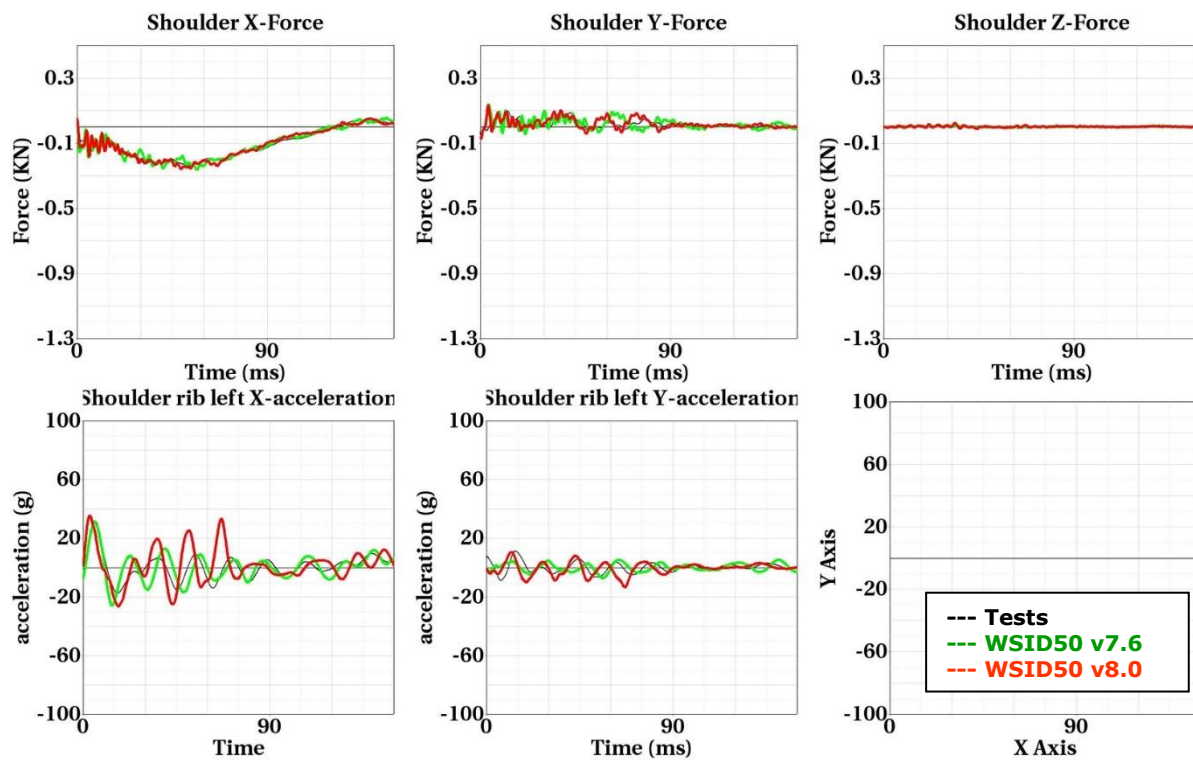


Figure 167: 180 Degree without sternum – low velocity

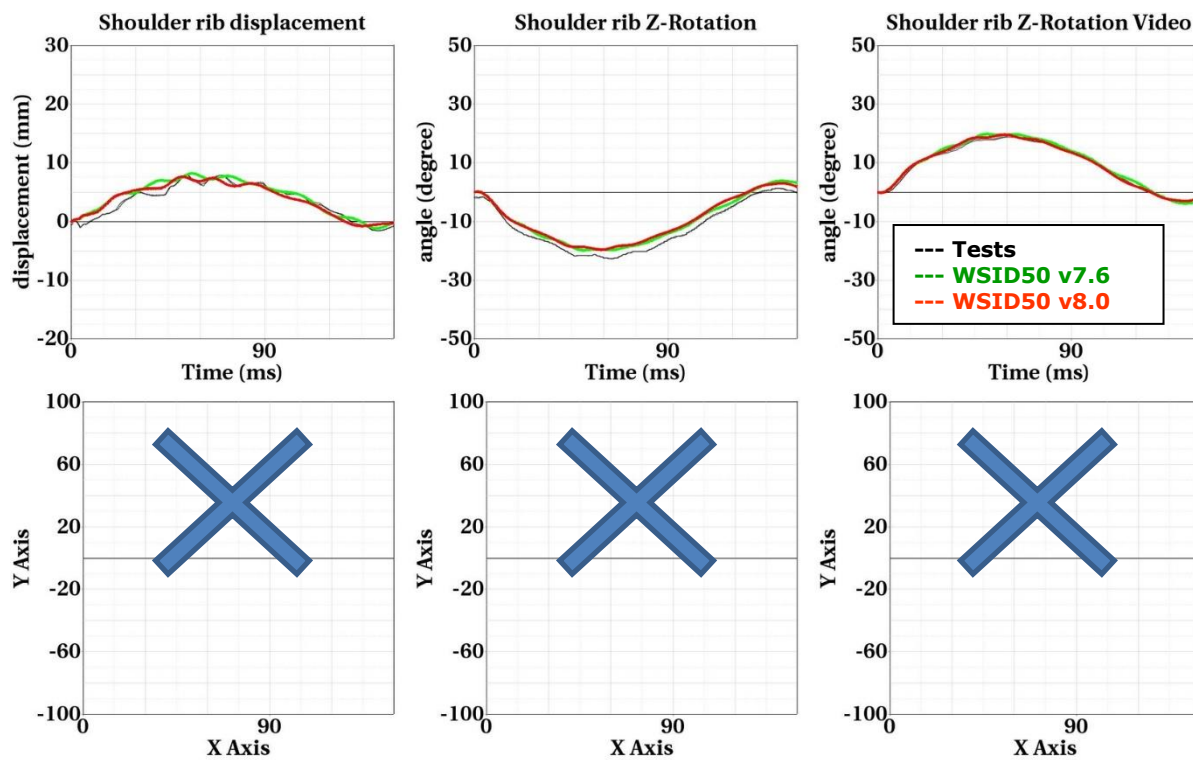


Figure 168: 180 Degree without sternum – low velocity

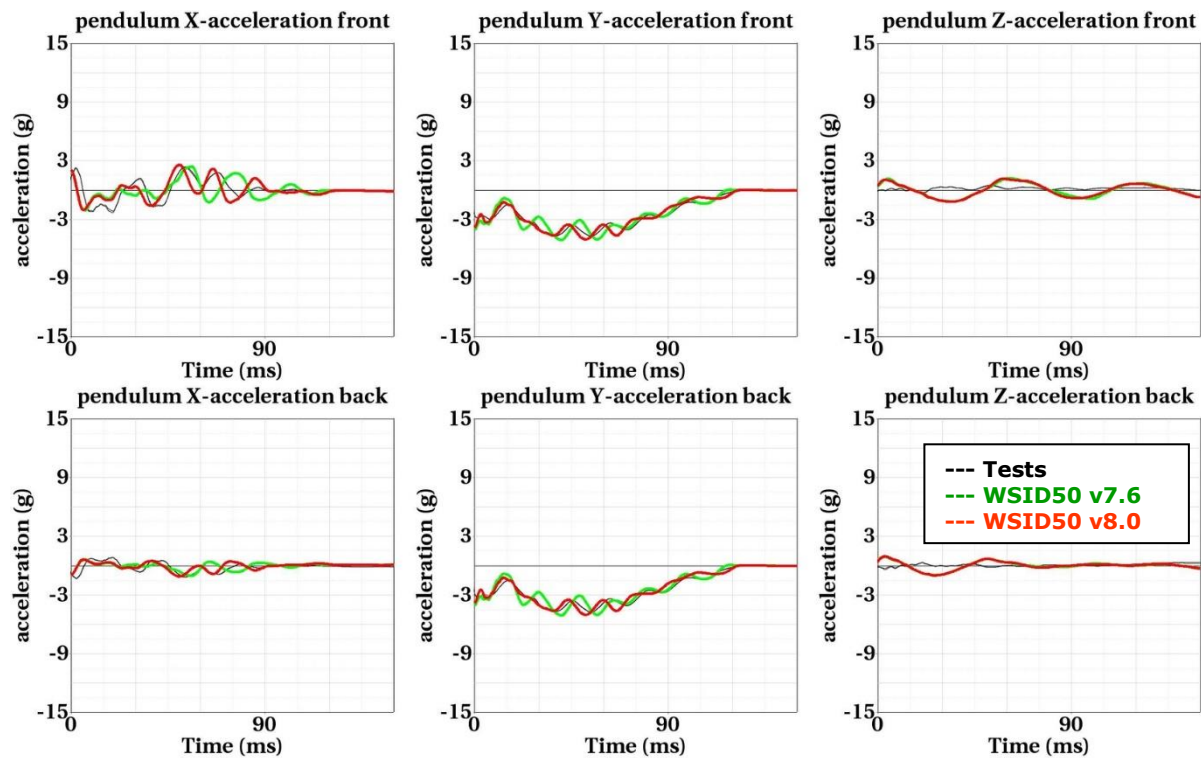


Figure 169: 180 Degree without sternum – low velocity

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

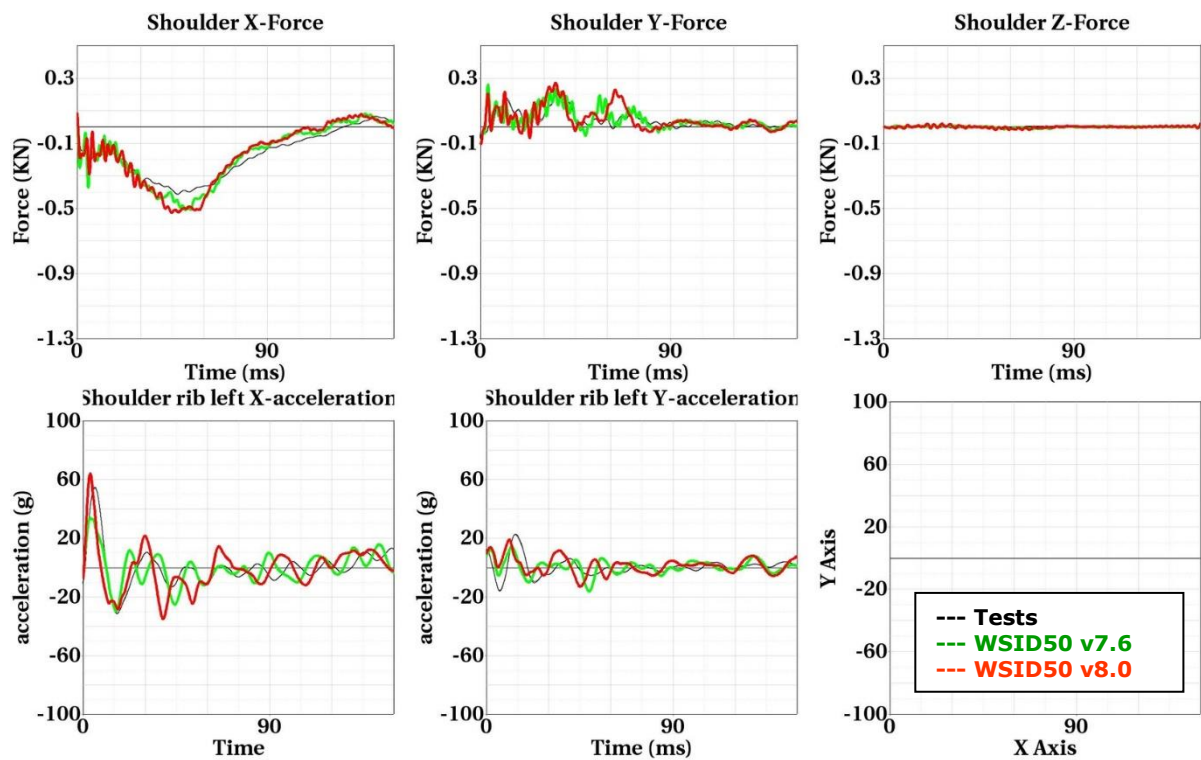


Figure 170: 180 Degree without sternum – high velocity

Performance – component tests

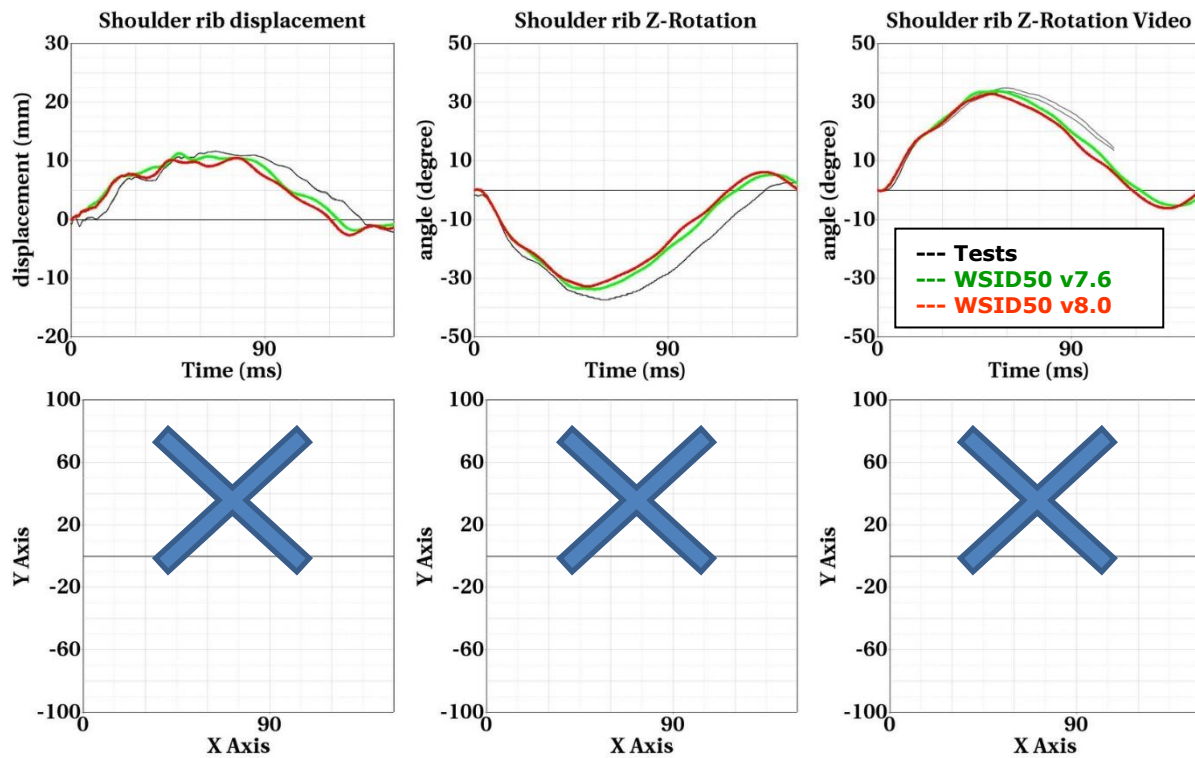


Figure 171: 180 Degree without sternum – high velocity

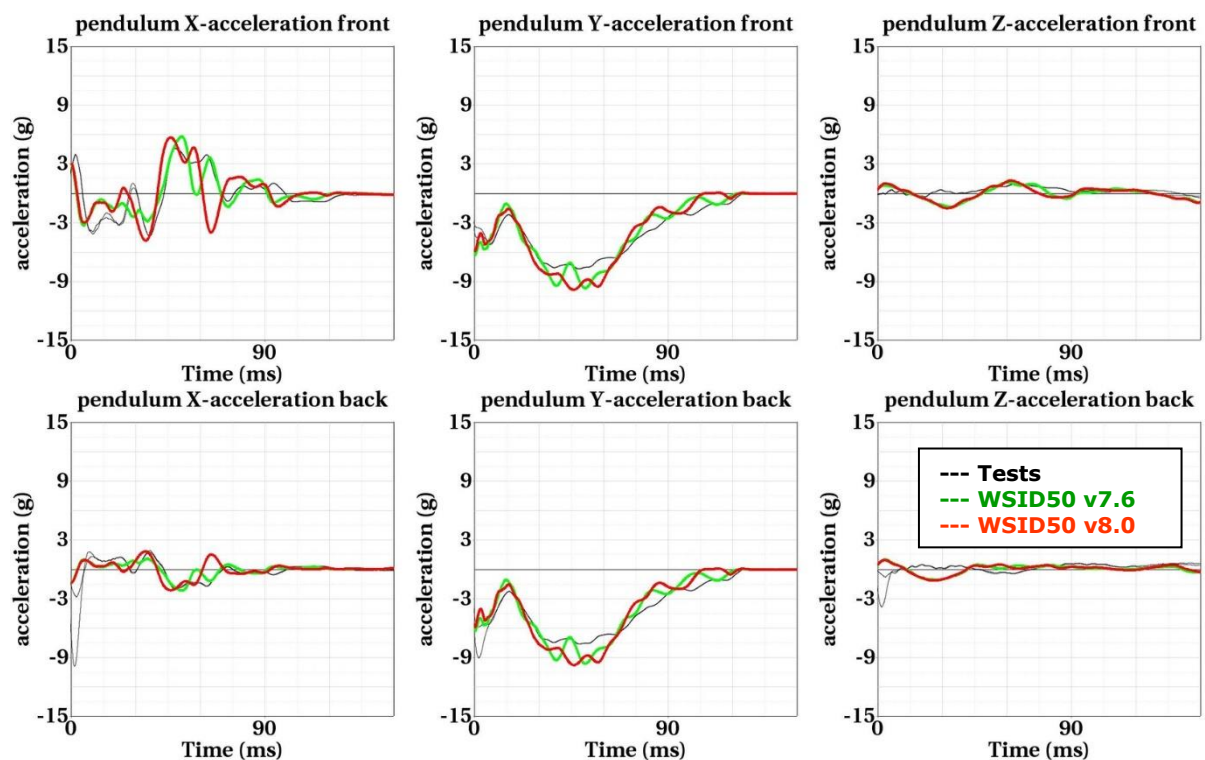


Figure 172: 180 Degree without sternum – high velocity

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.

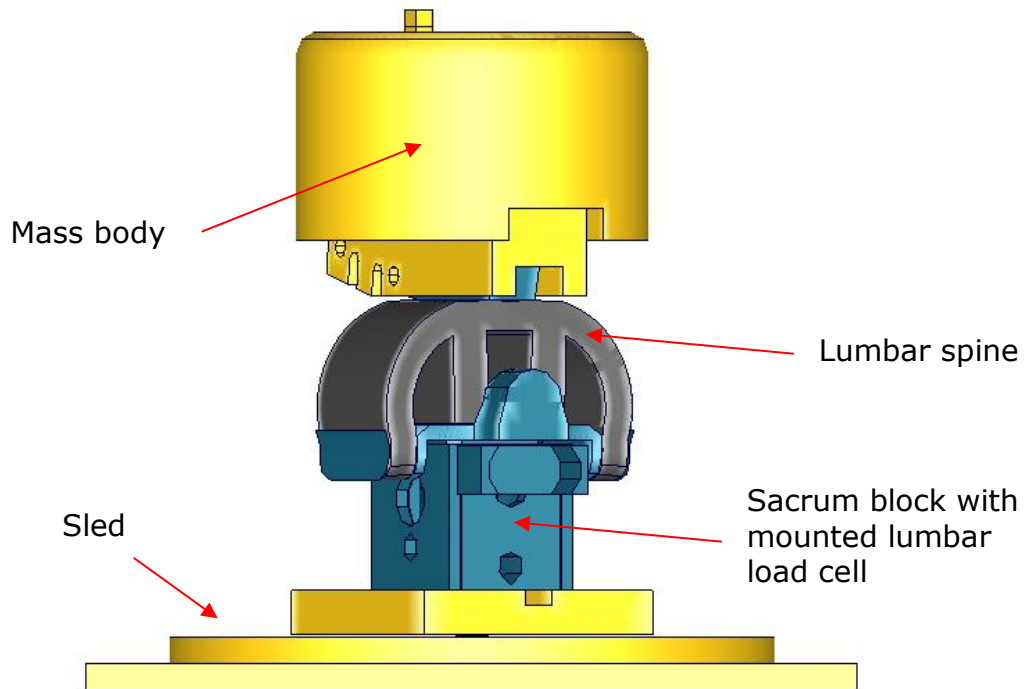


Figure 173: Lumbar spine component test setup

The lumbar spine test is done in two different angles. The angles are 90 and 60 degrees. A pulse of 35 g in y-direction was used for both setups.. The test configurations are listed in the Table 42.

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

Table 42: Test configurations for lumbar spine test

Results of 90 degree, 35g configuration:

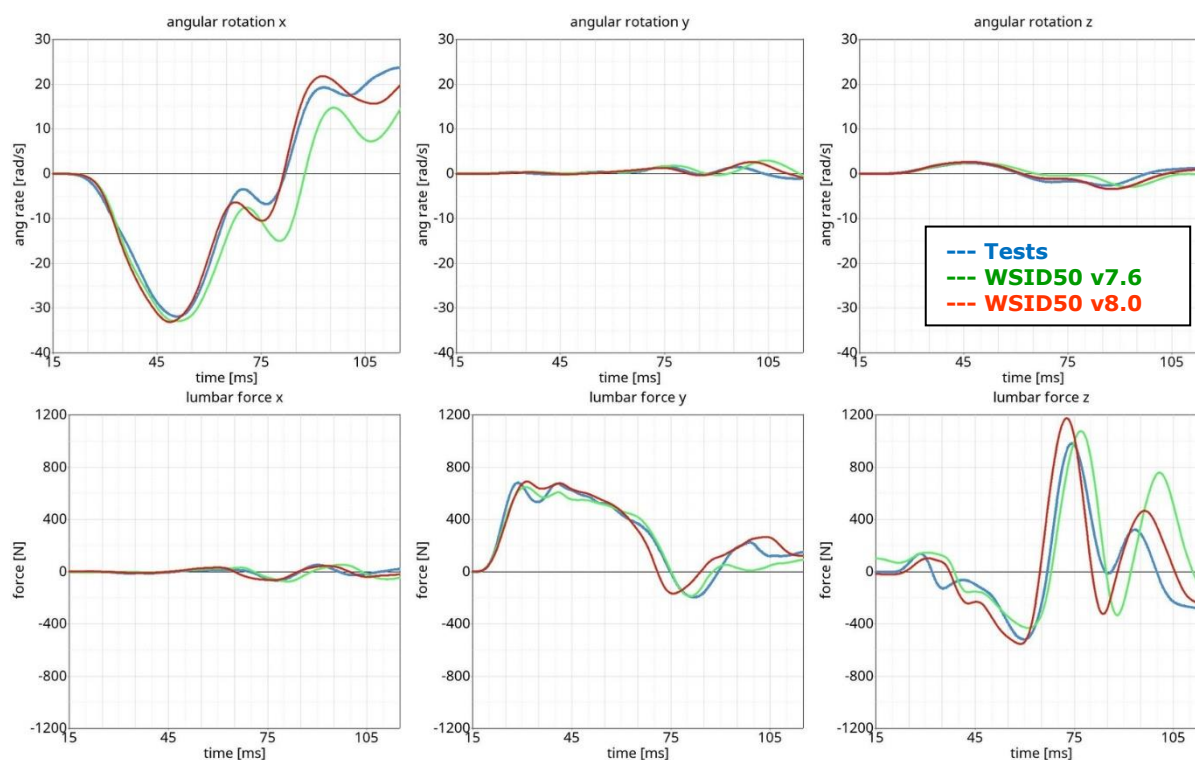


Figure 174: Result of lumbar spine test -- 35g, 90 degree

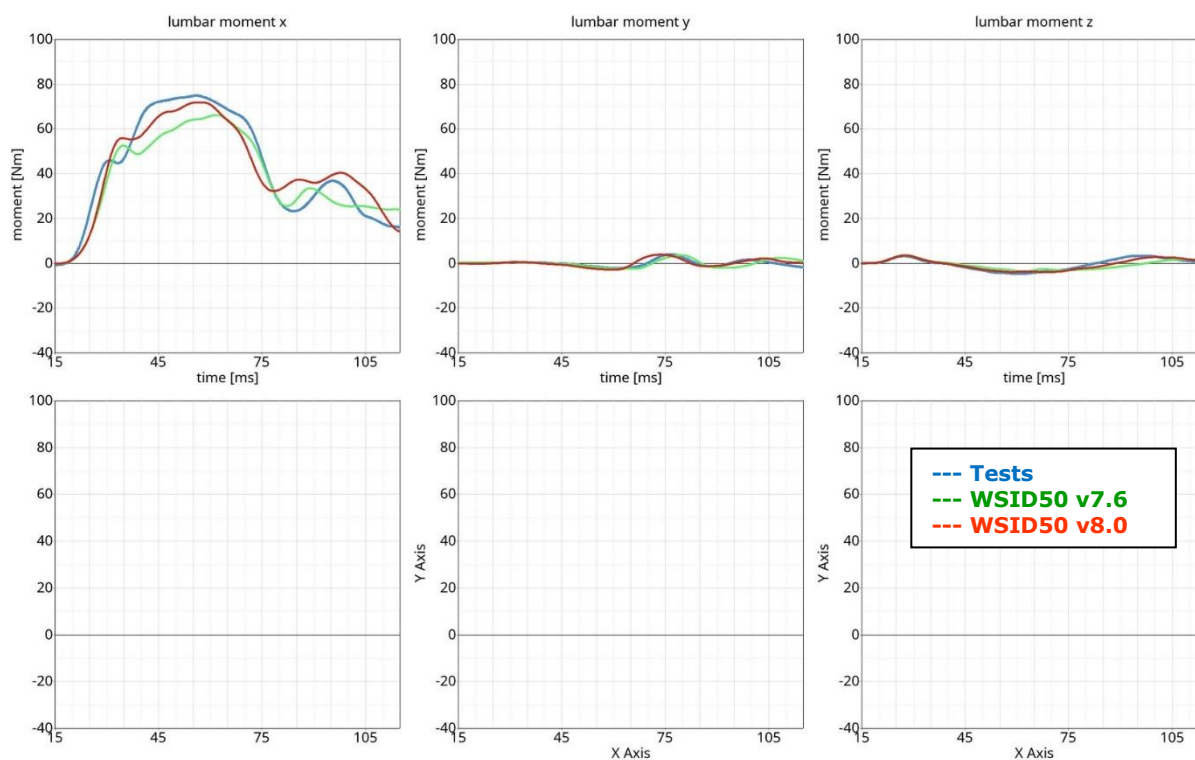


Figure 175: Result of lumbar spine test -- 35g, 90 degree

Results of 60 degree, 35g configuration:

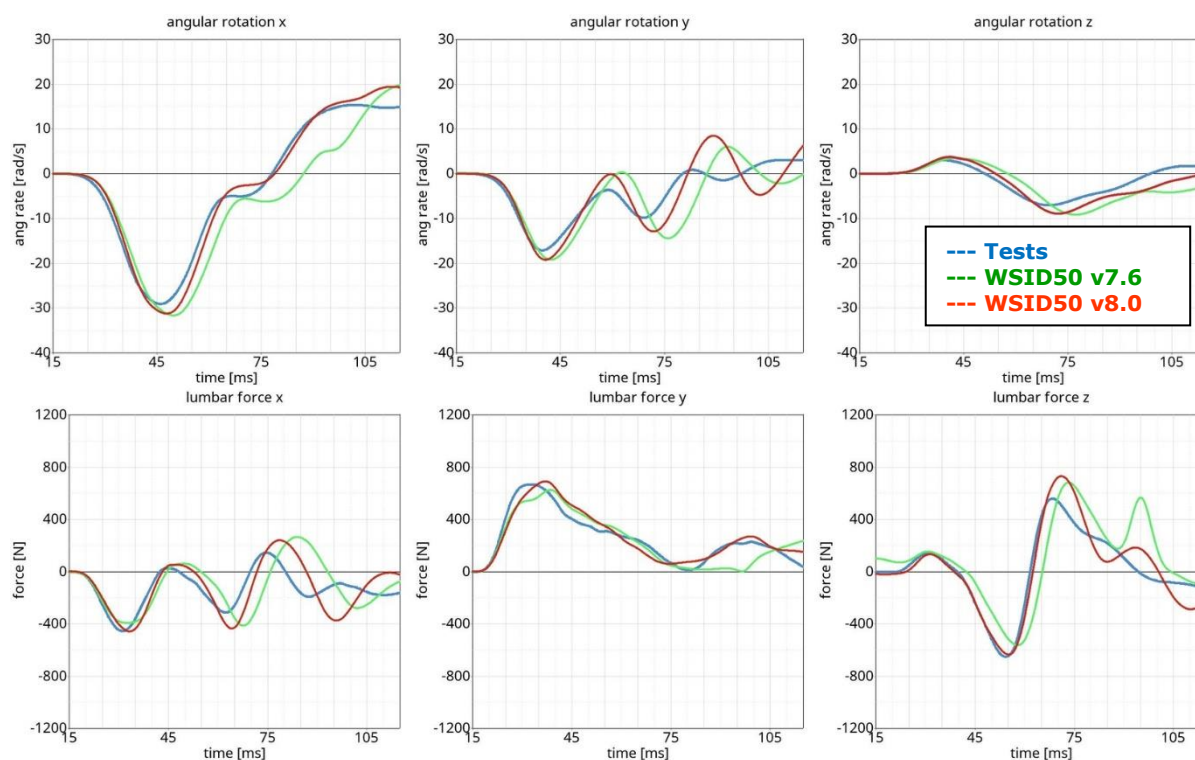


Figure 176: Result of lumbar spine test -- 35g, 60 degree

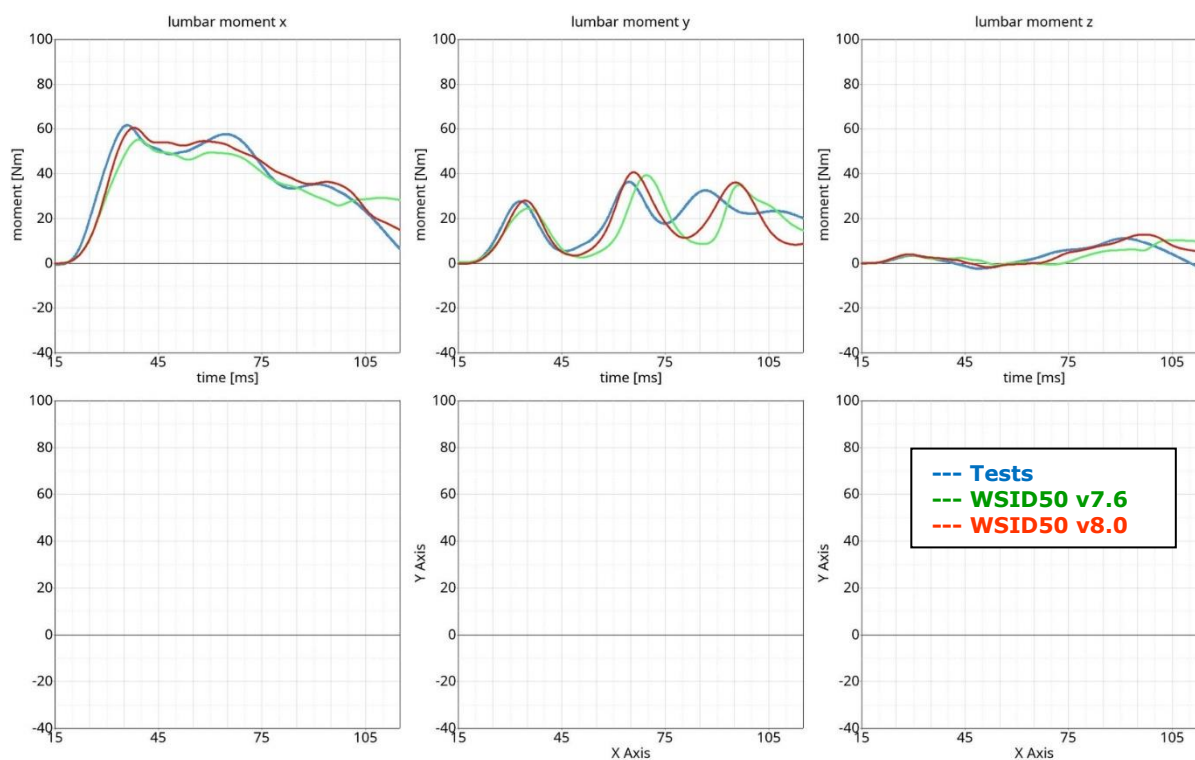


Figure 177: Result of lumbar spine test -- 35g, 60 degree

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.

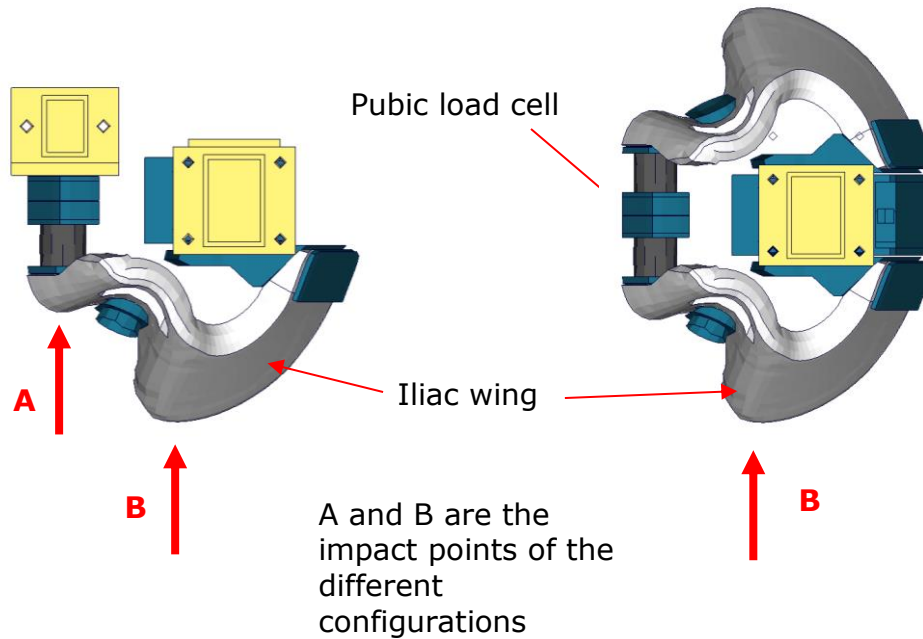


Figure 178: Iliac wing component test configurations

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

Table 43: Test configurations for iliac wing test

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

Pendulum accelerations

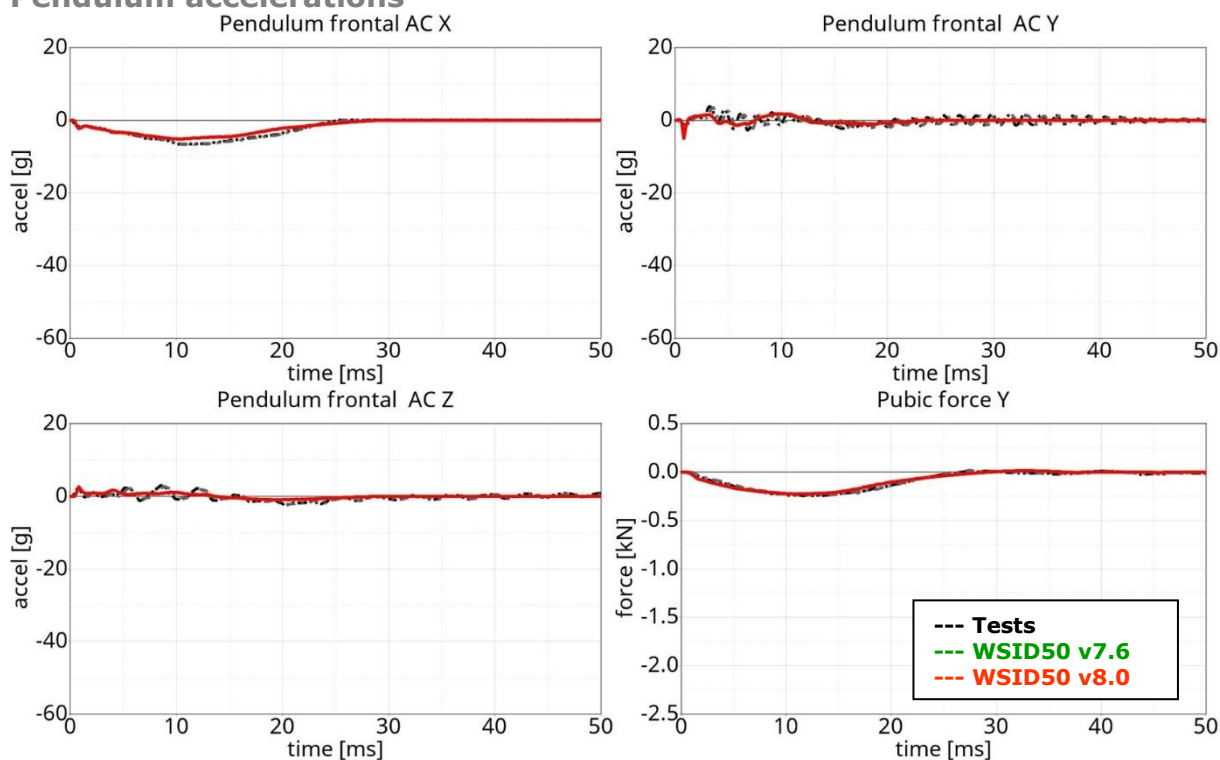


Figure 179: Result of iliac wing test -- Target point A, low velocity, half pelvis (Pendulum accelerations)

Sacro-iliac load cell

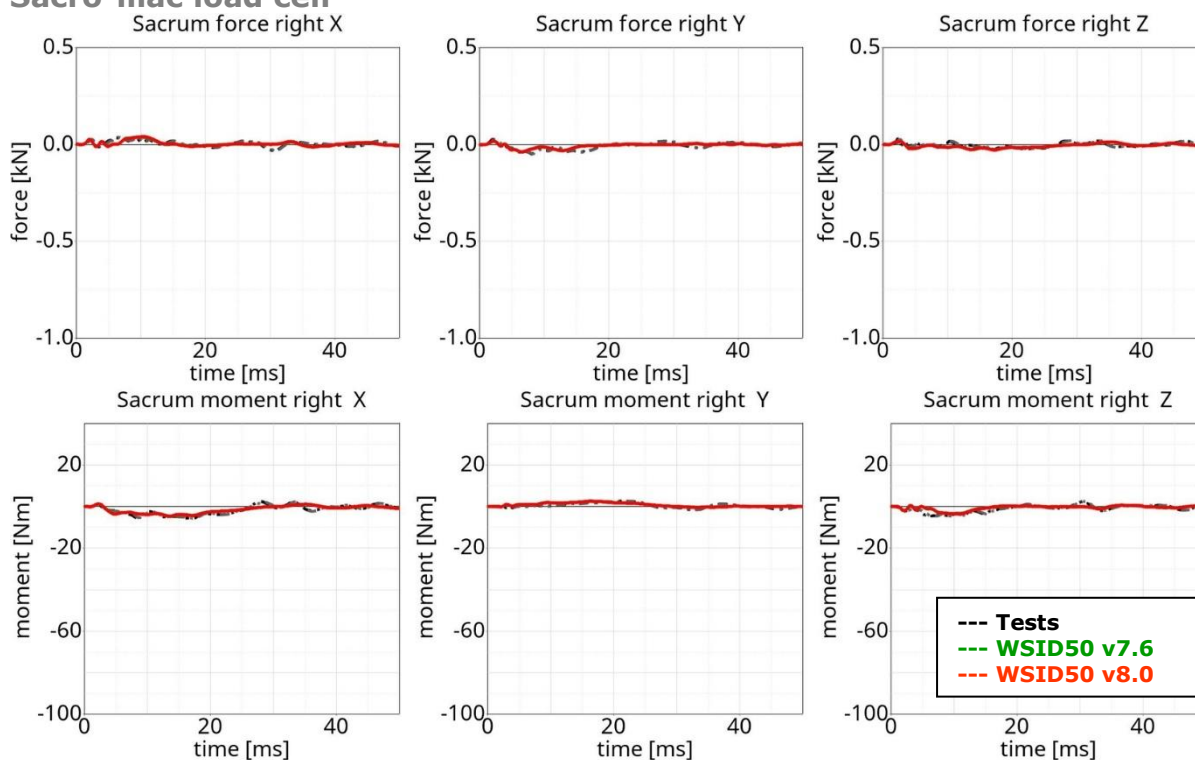


Figure 180: Result of iliac wing test -- Target point A, low velocity, half pelvis (Sacro-iliac load cell)

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

Pendulum accelerations

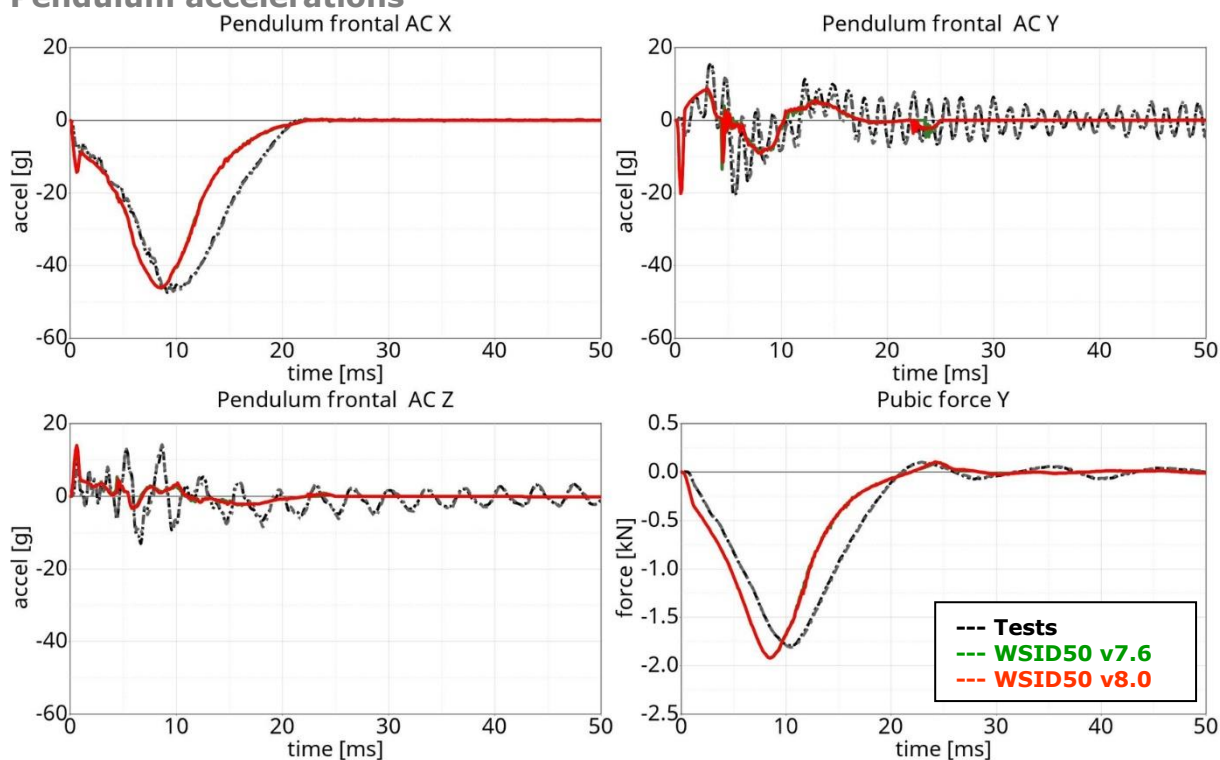


Figure 181: Result of iliac wing test -- Target point A, high velocity, half pelvis (Pendulum accelerations)

Sacro-iliac load cell

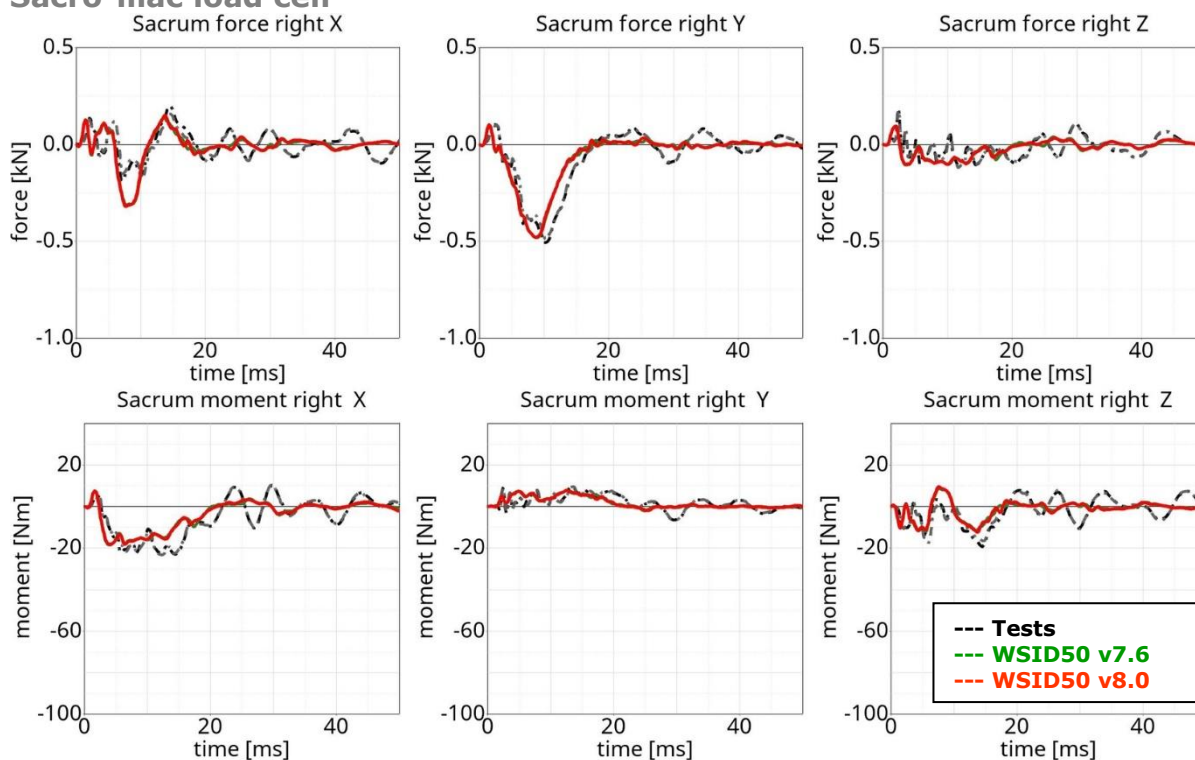


Figure 182: Result of iliac wing test -- Target point A, high velocity, half pelvis (Sacro-iliac load cell)

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

Pendulum accelerations

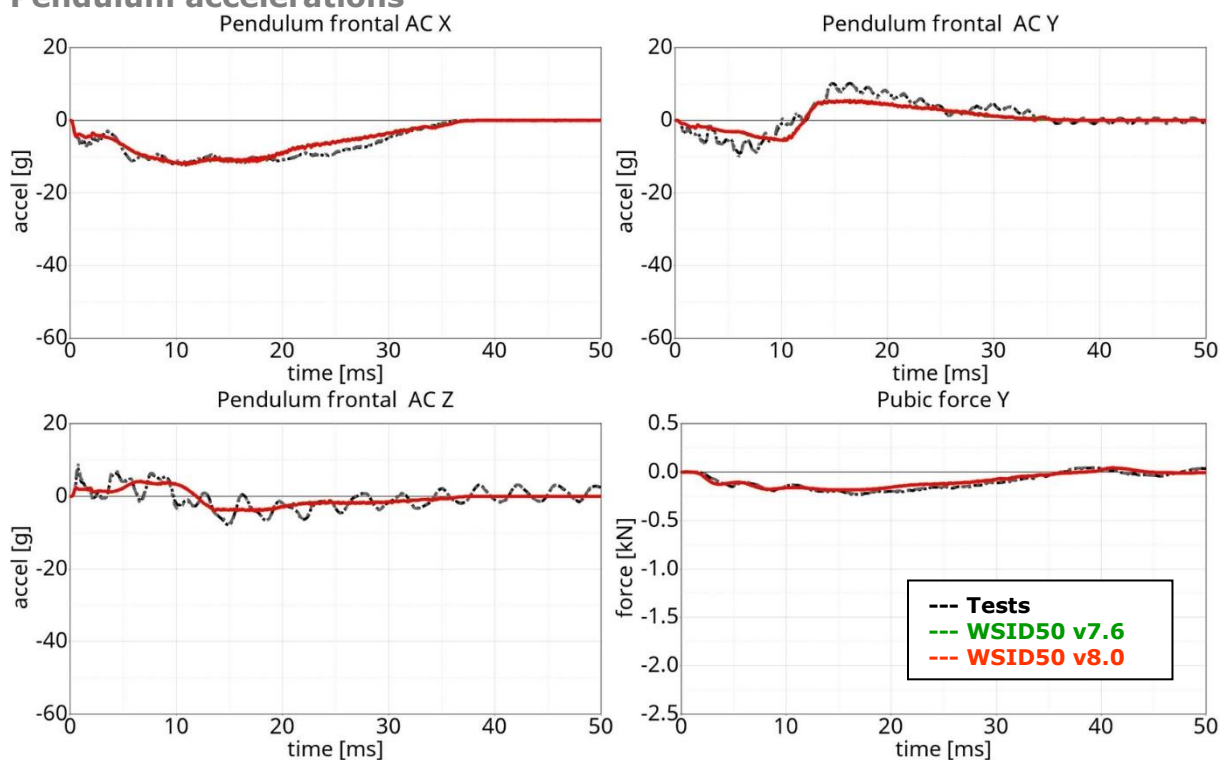


Figure 183: Result of iliac wing test -- Target point B, low velocity, half pelvis (Pendulum accelerations)

Sacro-iliac load cell

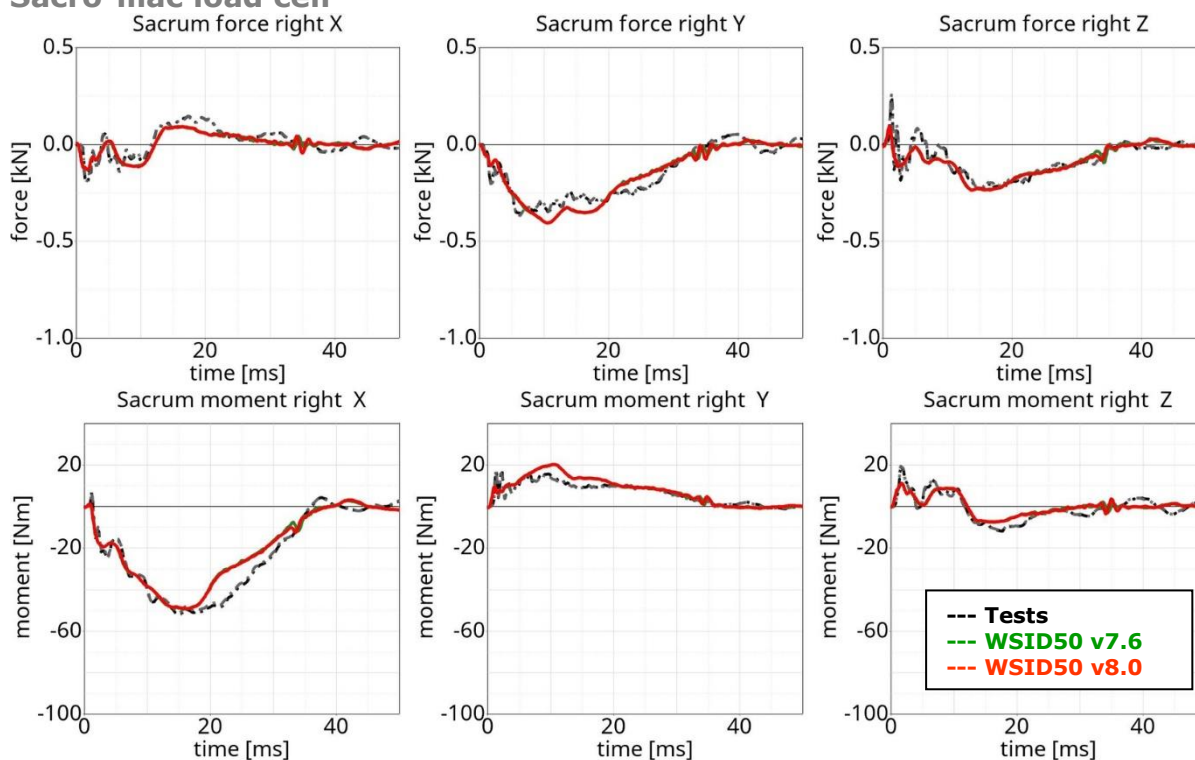


Figure 184: Result of iliac wing test -- Target point B, low velocity, half pelvis (Sacro-iliac load cell)

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

Pendulum accelerations

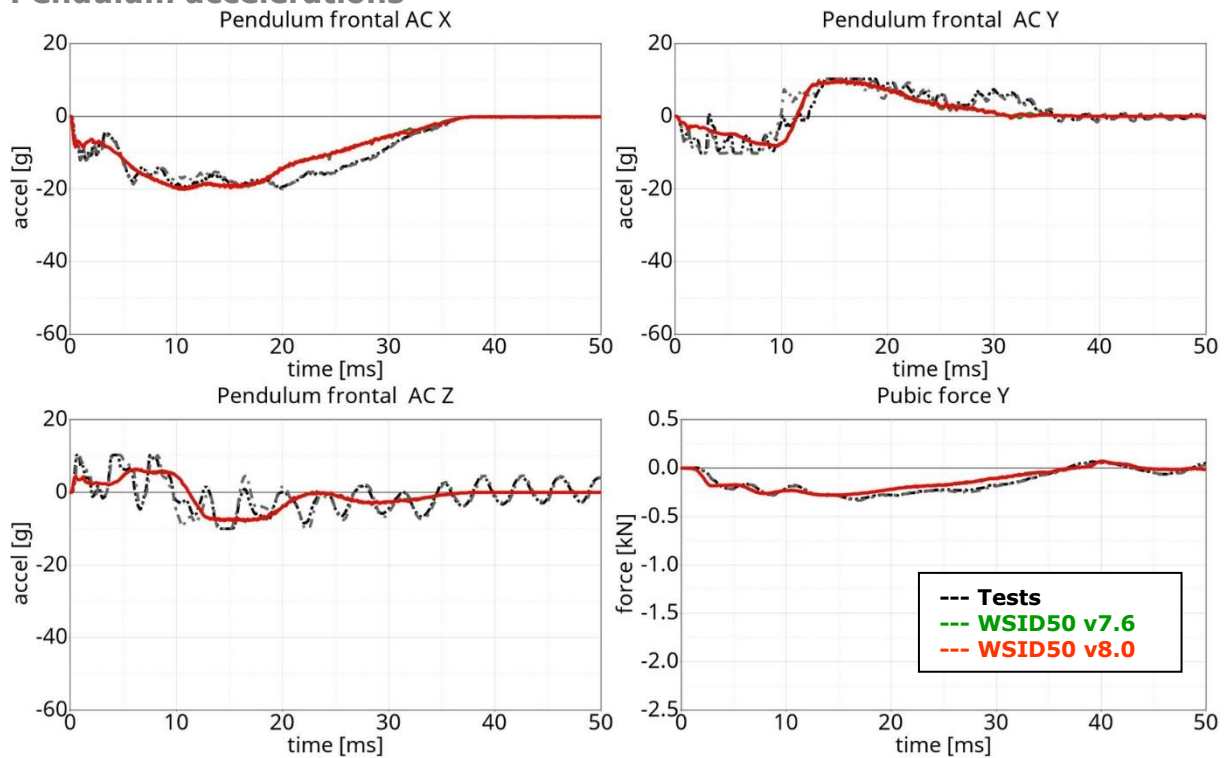


Figure 185: Result of iliac wing test -- Target point B, high velocity, half pelvis (Pendulum accelerations)

Sacro-iliac load cell

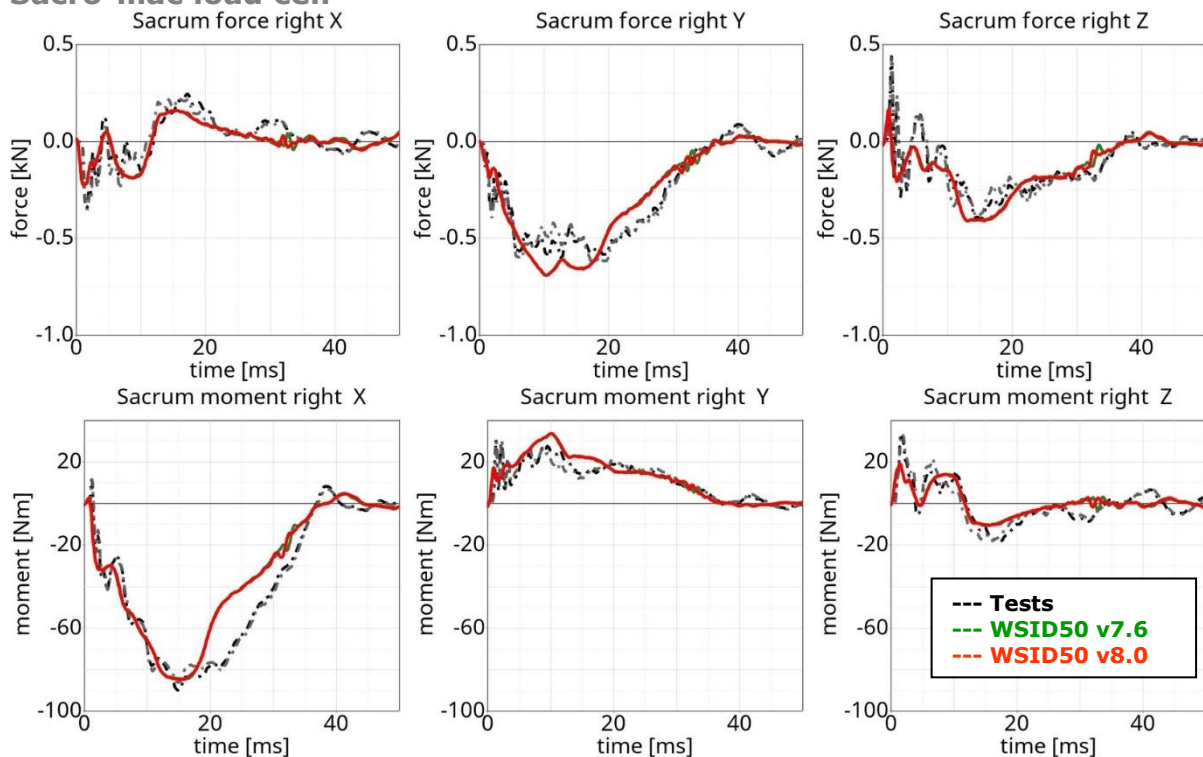


Figure 186: Result of iliac wing test -- Target point B, high velocity, half pelvis (Sacro-iliac load cell)

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

Pendulum accelerations

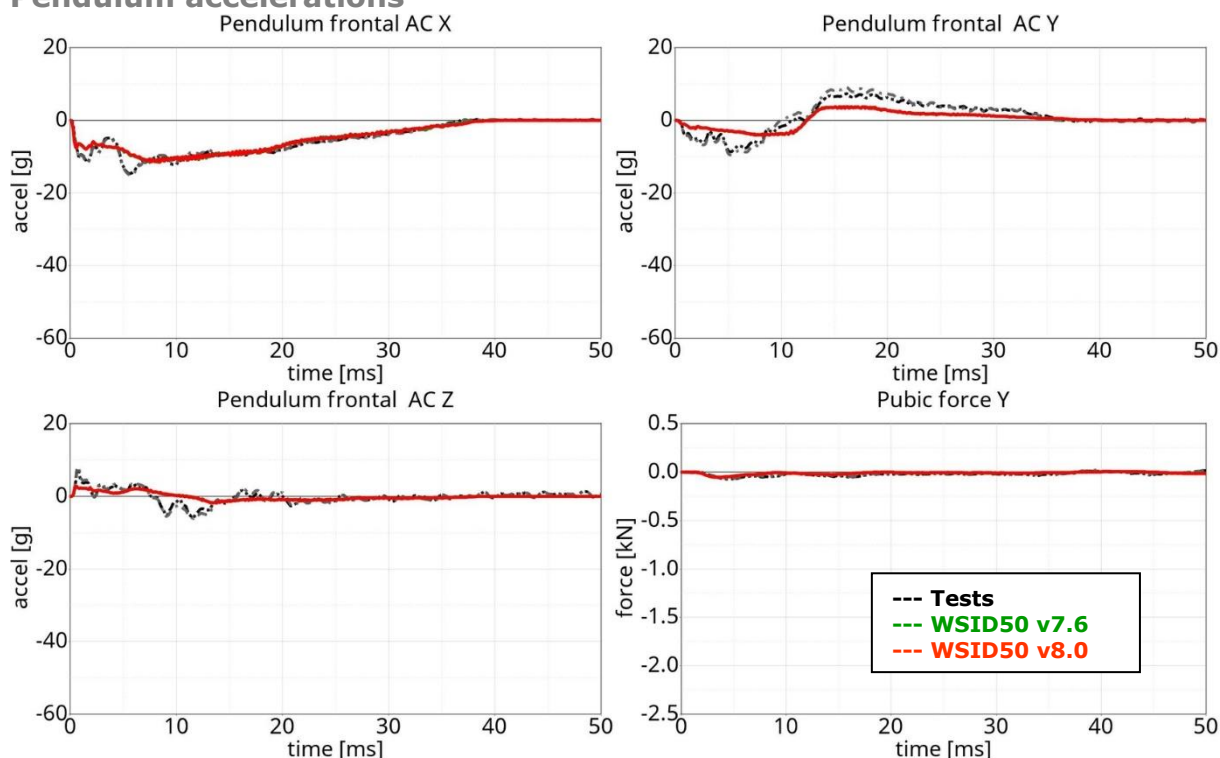


Figure 187: Result of iliac wing test -- Target point B, low velocity, full pelvis (Pendulum accelerations)

Sacro-iliac load cell

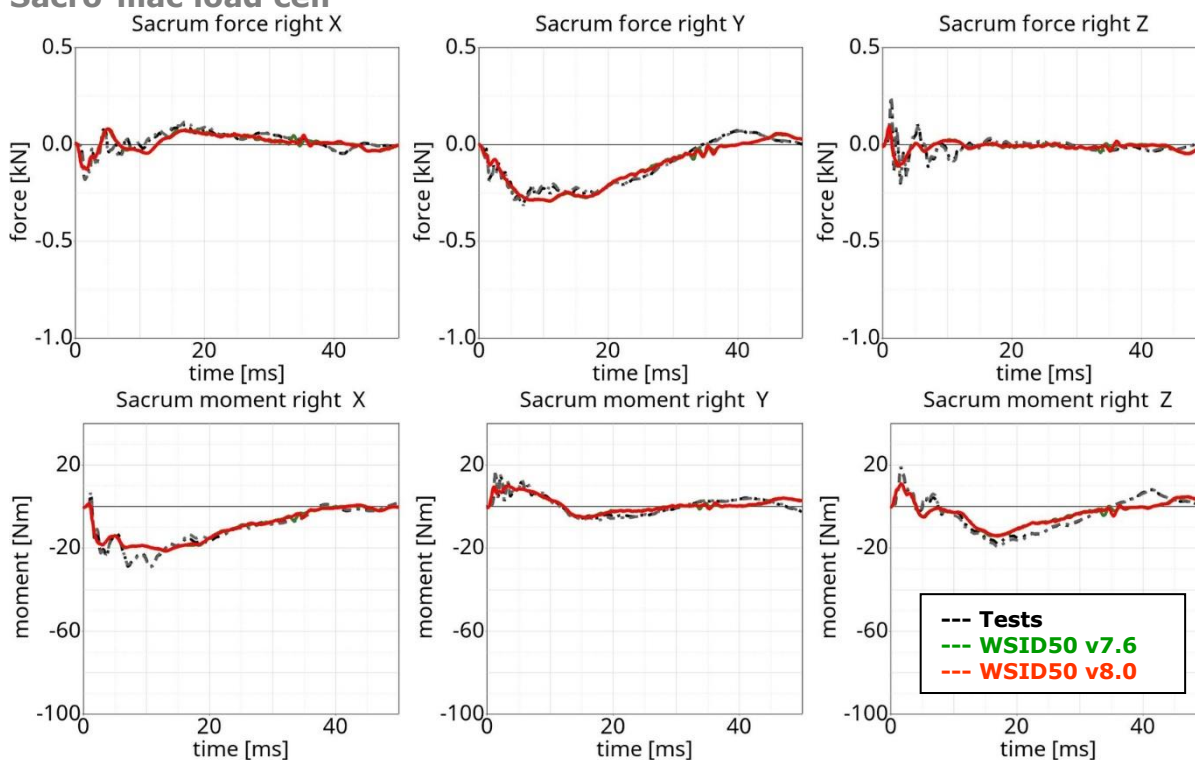


Figure 188: Result of iliac wing test -- Target point B, low velocity, full pelvis (Sacro-iliac load cell)

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

Pendulum accelerations

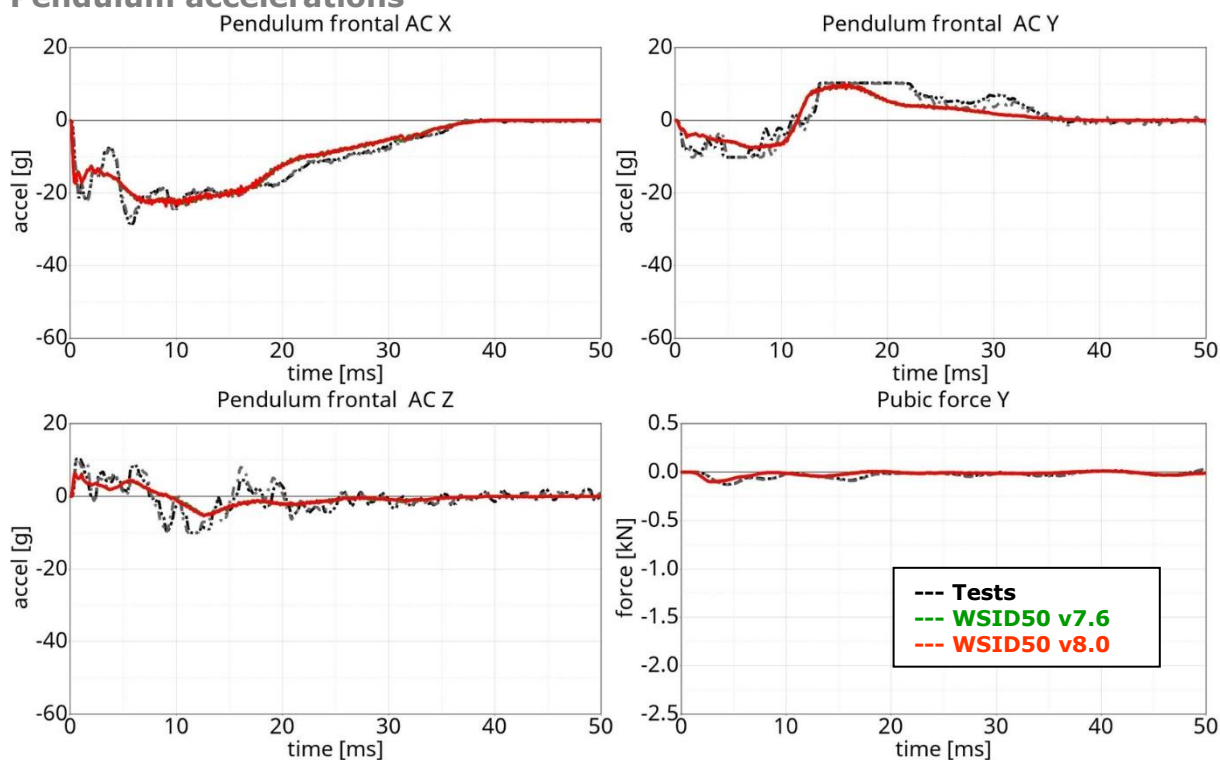


Figure 189: Result of iliac wing test -- Target point B, high velocity, full pelvis (Pendulum accelerations)

Sacro-iliac load cell

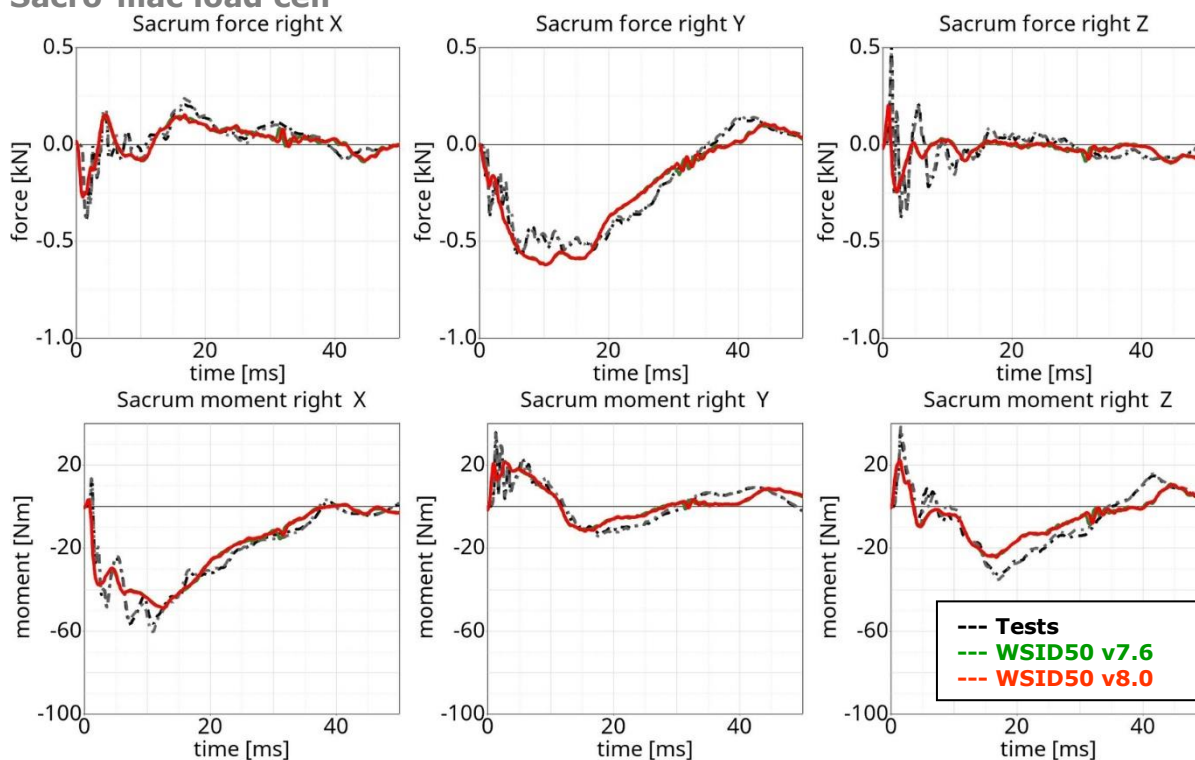


Figure 190: Result of iliac wing test -- Target point B, high velocity, full pelvis (Sacro-iliac load cell)

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.

Since version 8.0 there is an optional stiffness parameter system for validation performance.

The purpose is to get different dummy performance base on dummy validation specifications (corridor).

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.

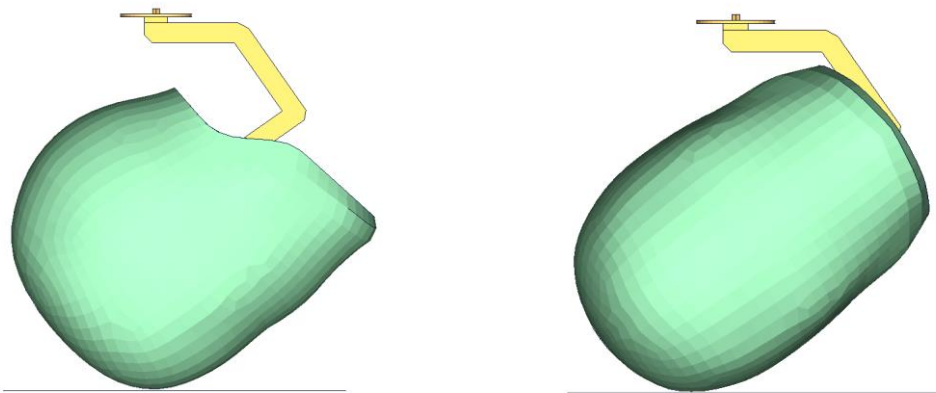


Figure 191: Head drop test, Left: Frontal test, Right: Lateral test

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

Results of frontal head drop test

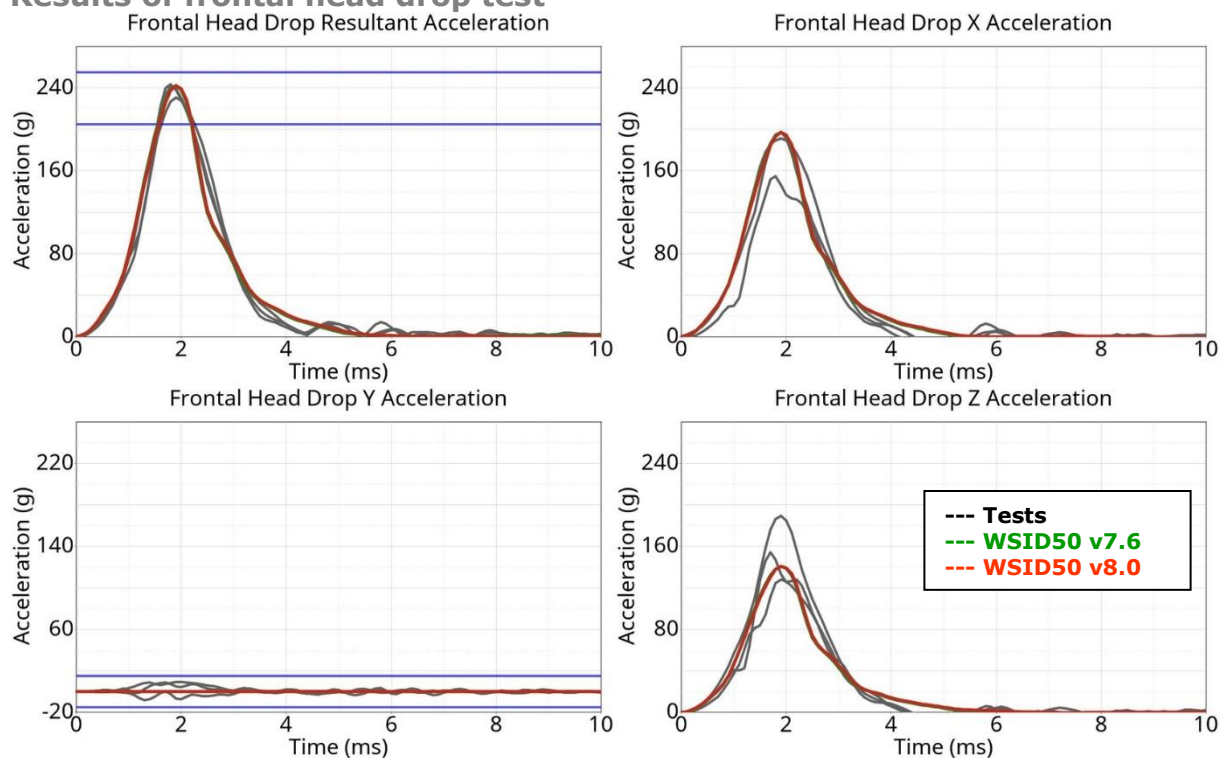


Figure 192: Results of frontal head drop test

Results of lateral head drop test

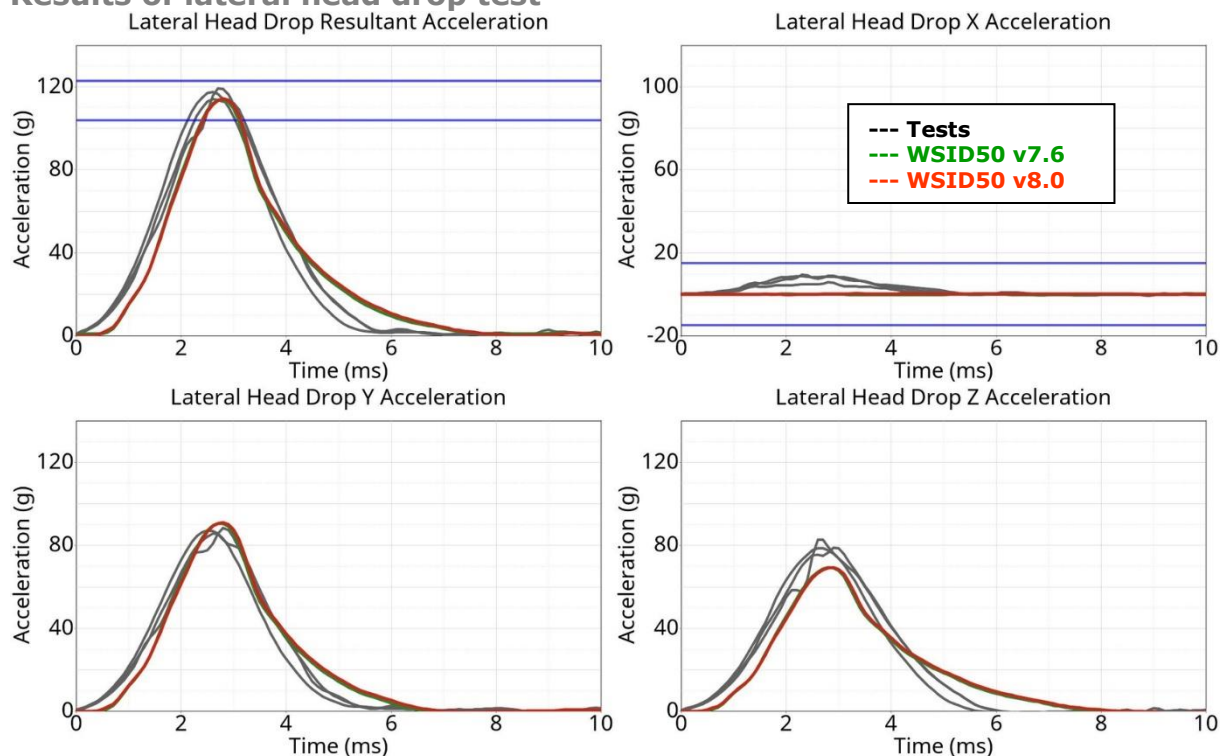


Figure 193: Results of lateral head drop test

Results of frontal head drop performance with &head_opt

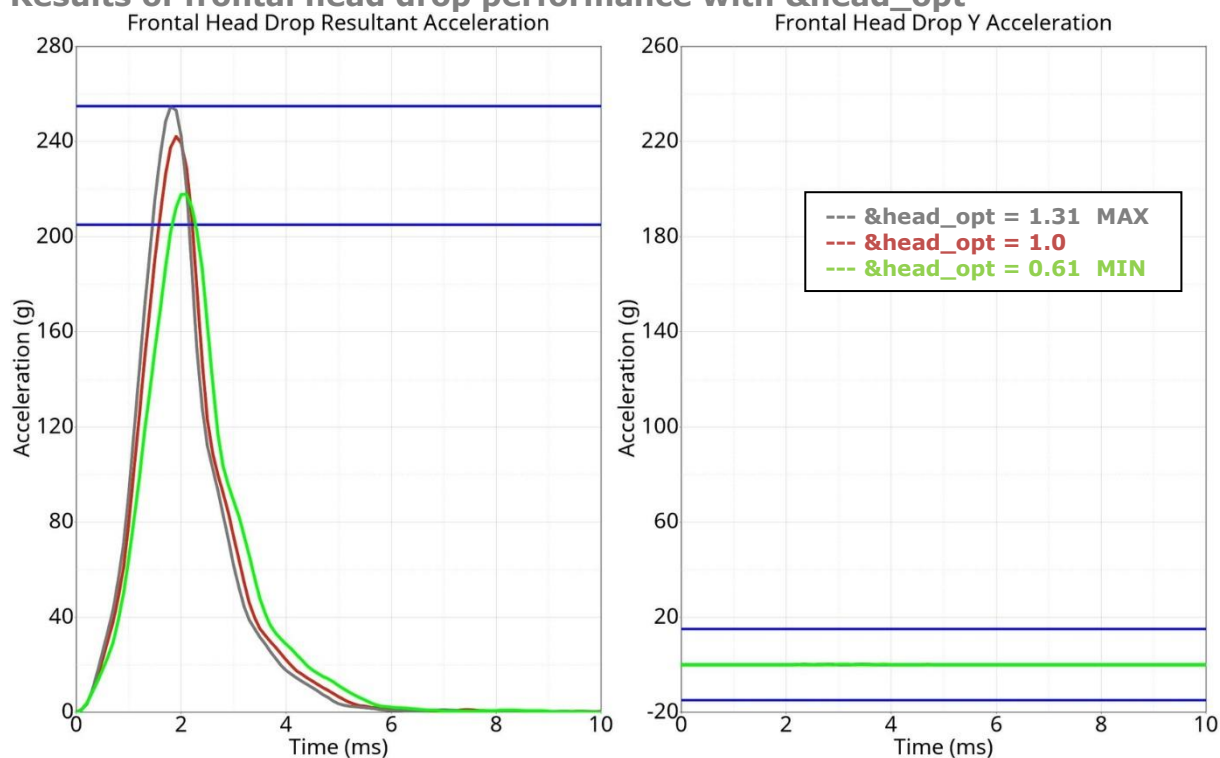


Figure 194: frontal head drop performance

Results of lateral head drop performance with &head_opt

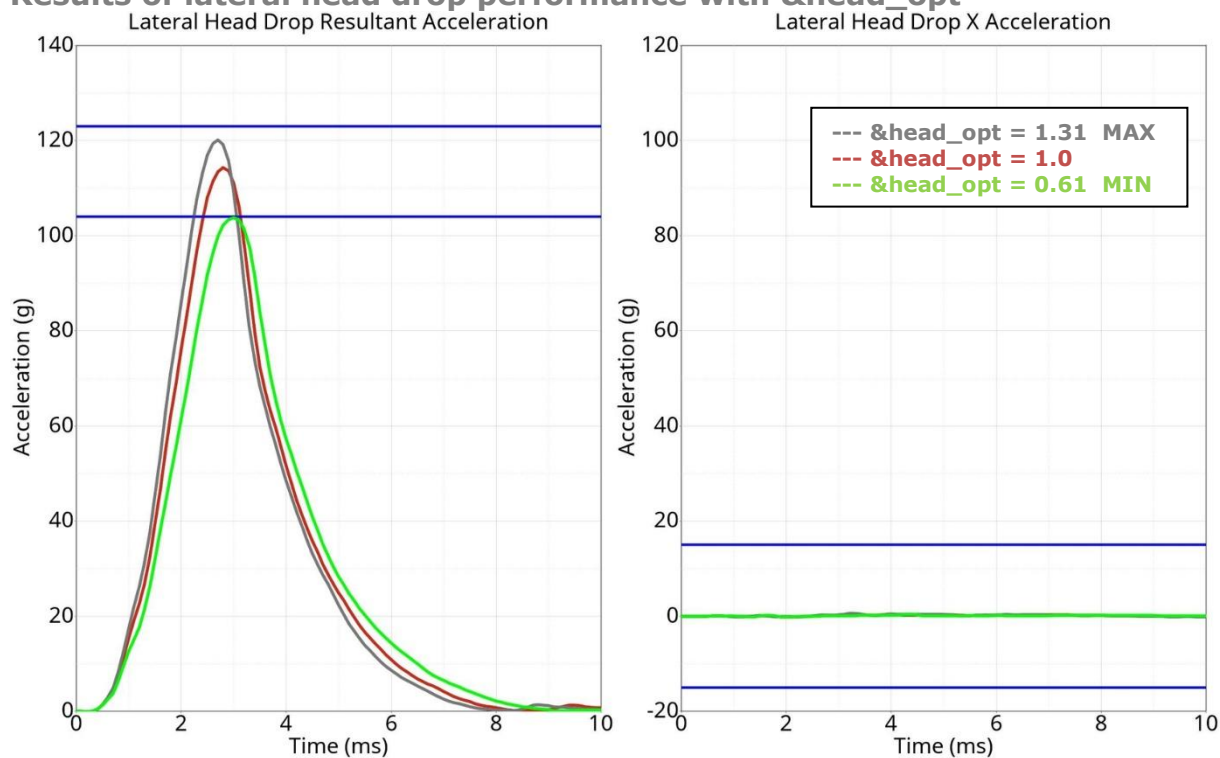


Figure 195: lateral head drop performance

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.

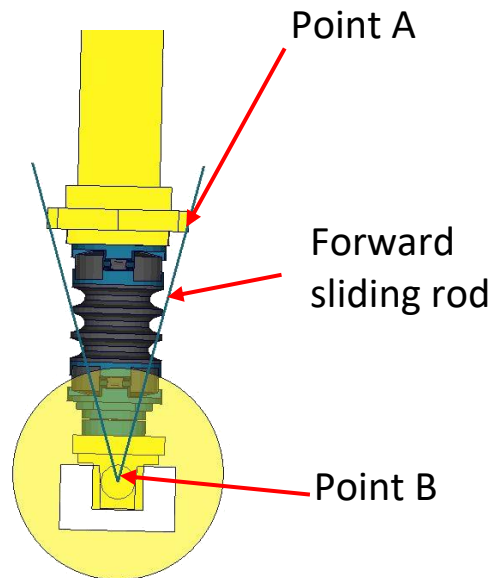


Figure 196: Neck pendulum calibration test setup

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.

Upper neck load cell results

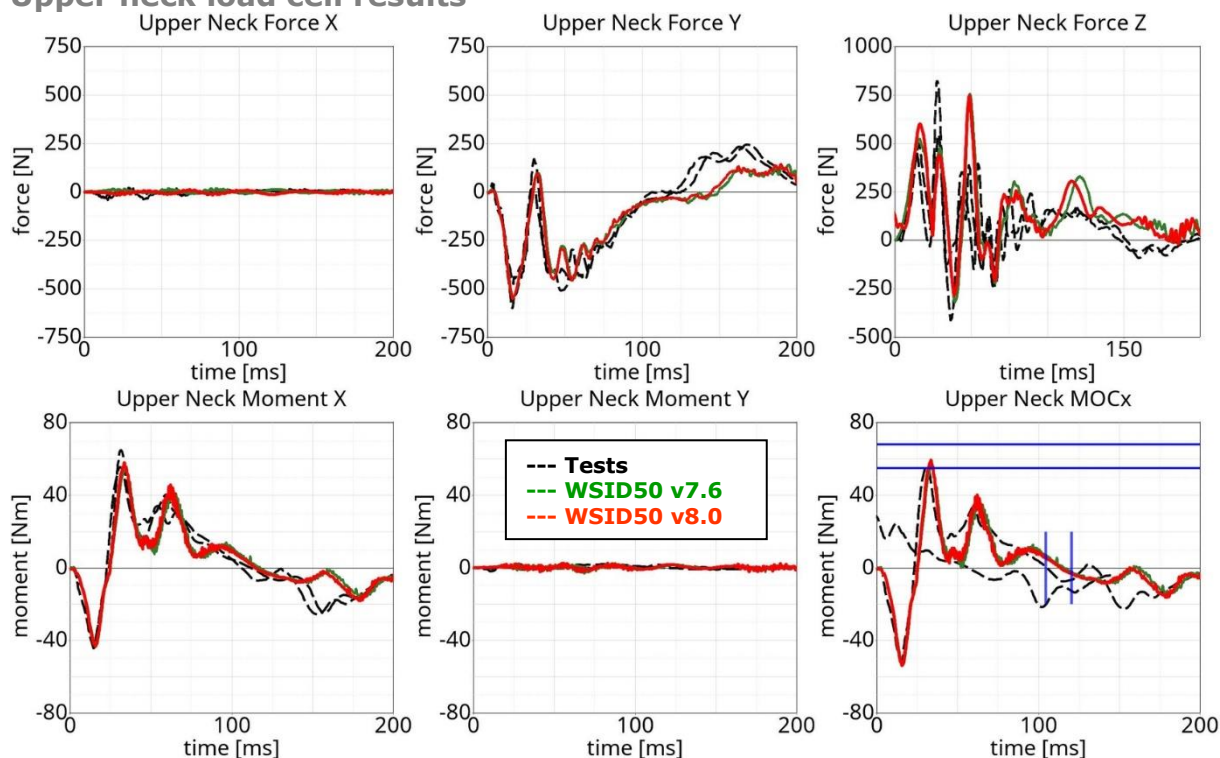


Figure 197: Result of neck calibration test upper neck load cell

Head form rotation results

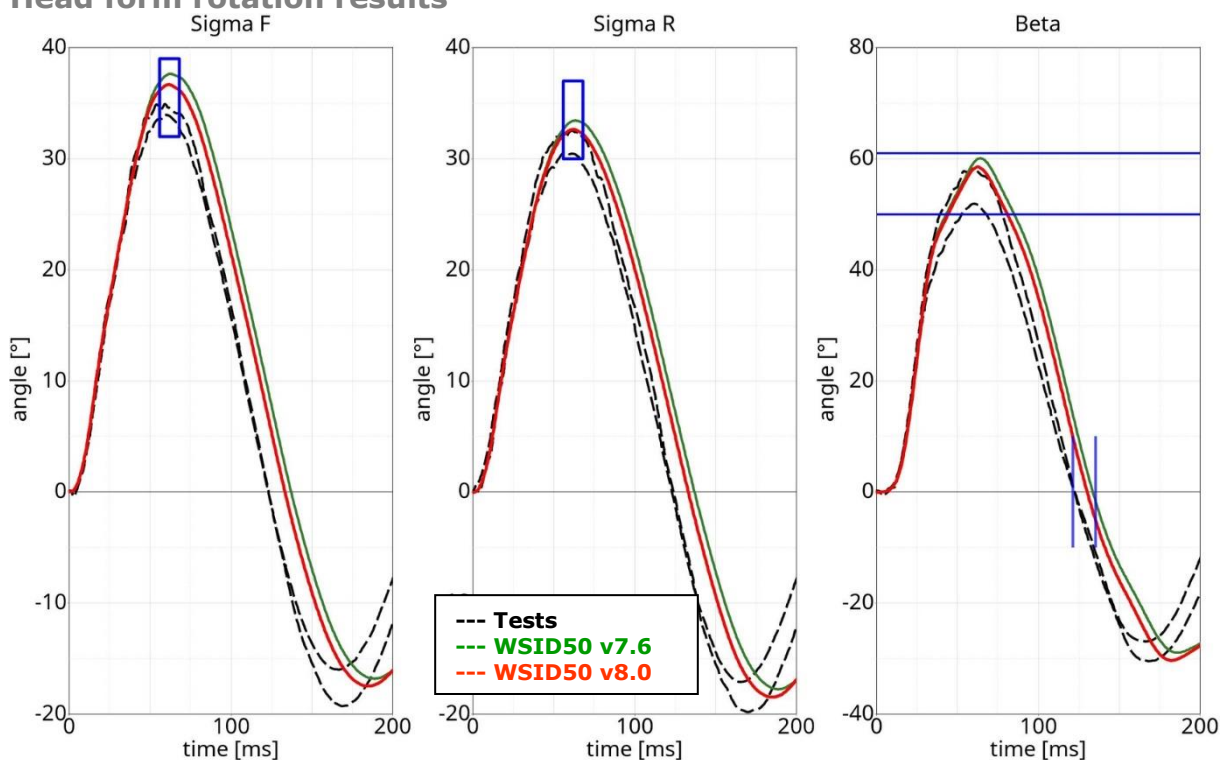


Figure 198: Result of neck calibration test head form rotations

Upper neck load cell performance with &neck_opt

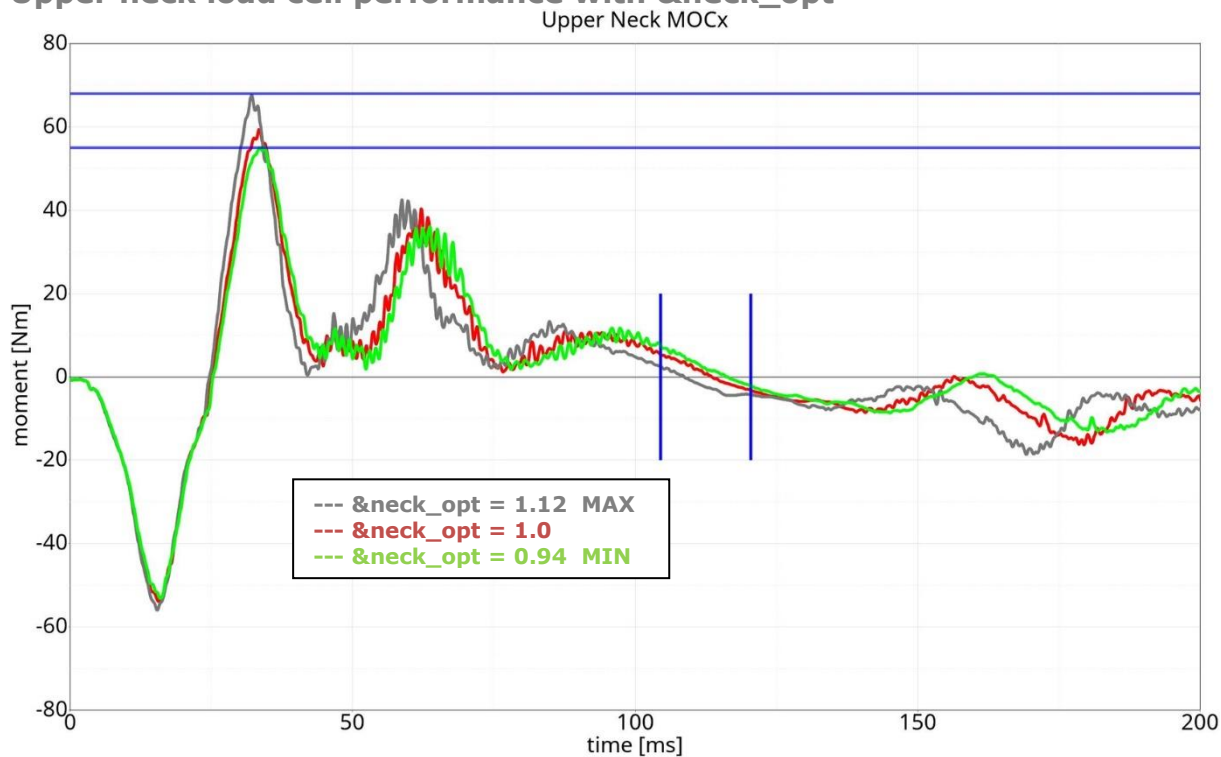


Figure 199: neck calibration performance

Head form rotation performance with &neck_opt

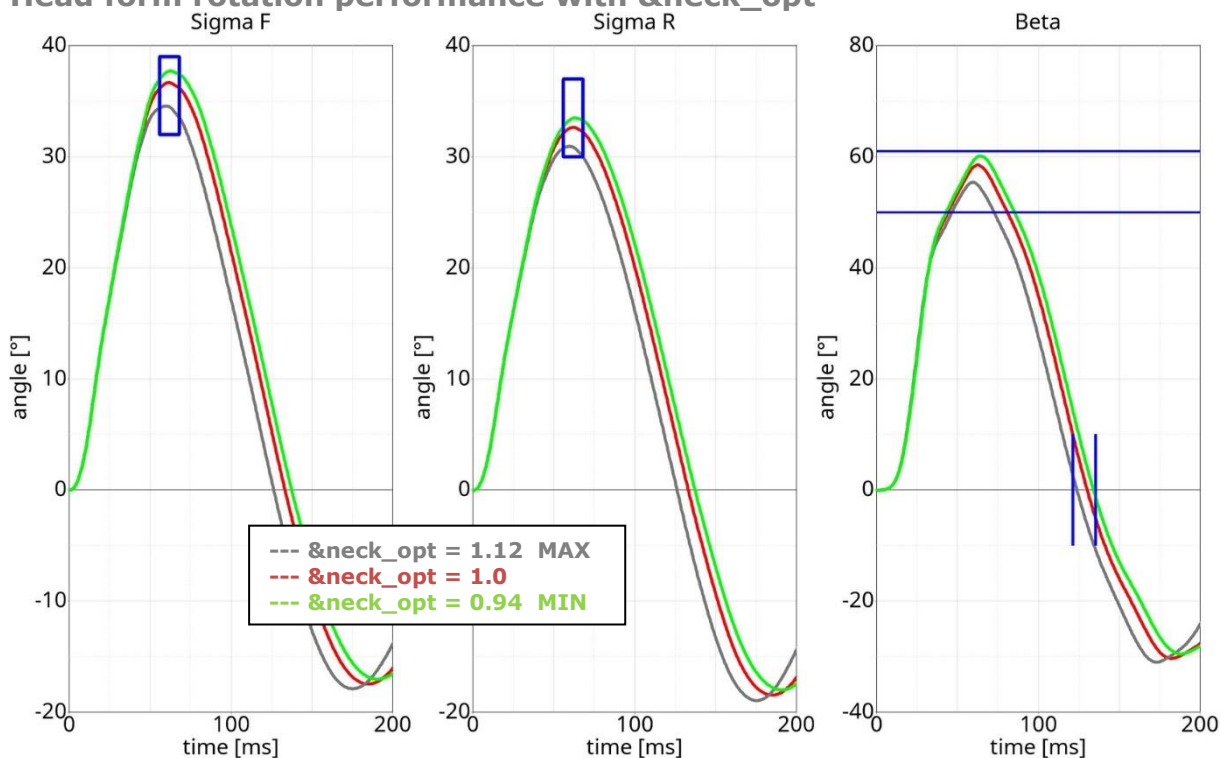


Figure 200: neck calibration performance

8.2.3 Neck torsion test

The neck torsion calibration test is simulated as described in the WorldSID ISO-15830 part 2. 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.

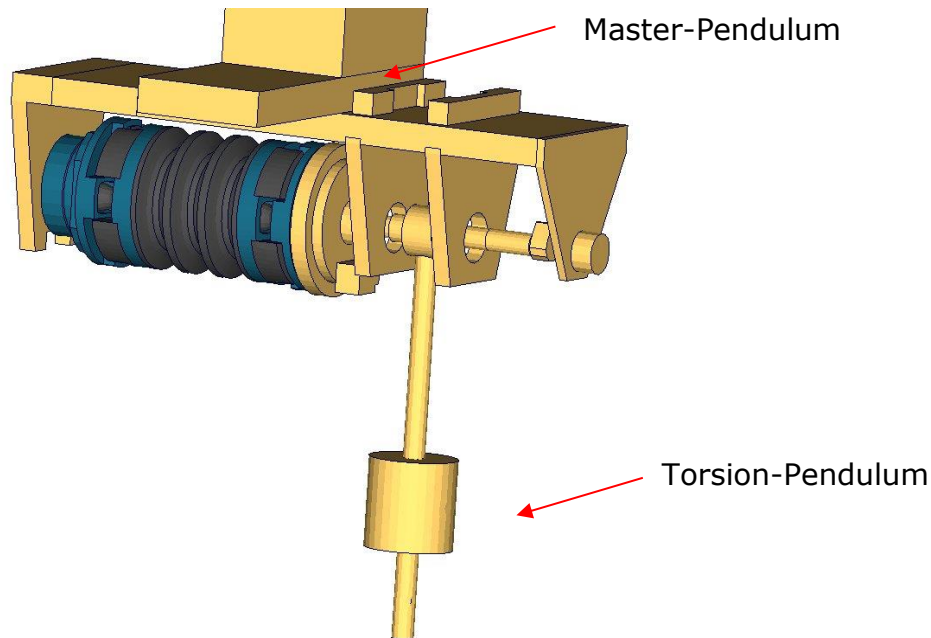


Figure 201: Neck torsion calibration test setup

Results of neck torsion calibration test (Page 1)

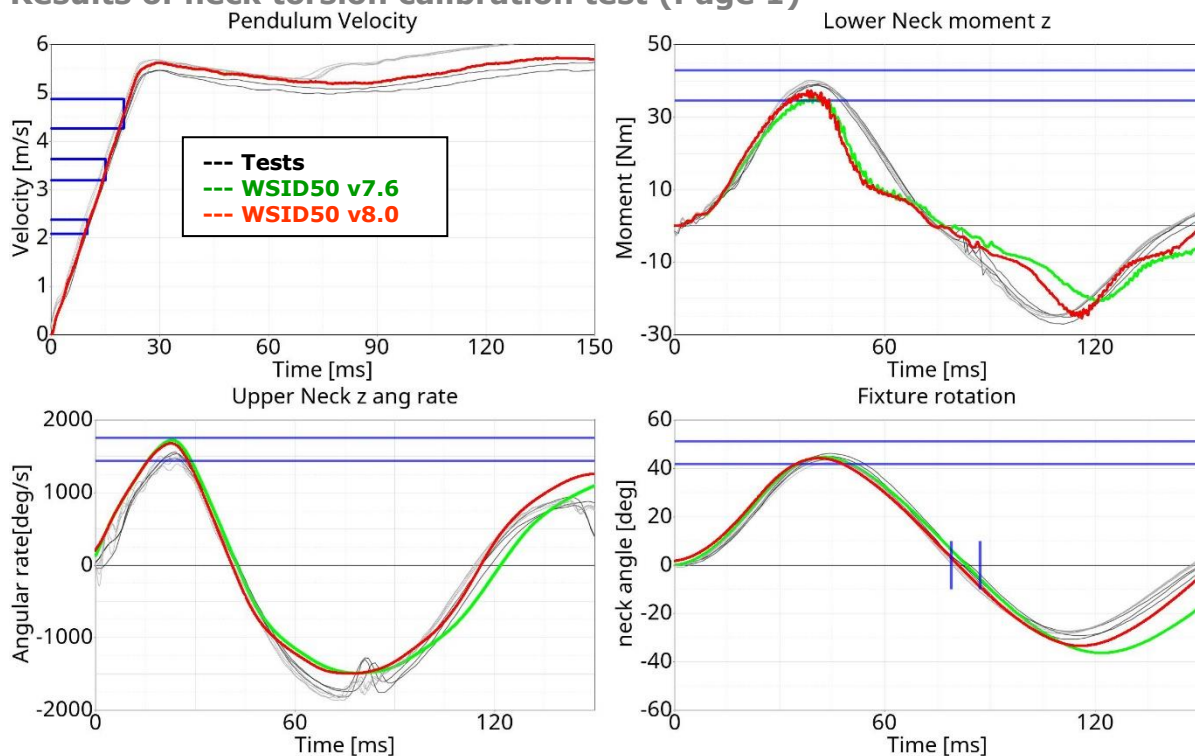


Figure 202: Neck torsion calibration test results (Page 1)

Results of neck torsion calibration performance with &neck_opt

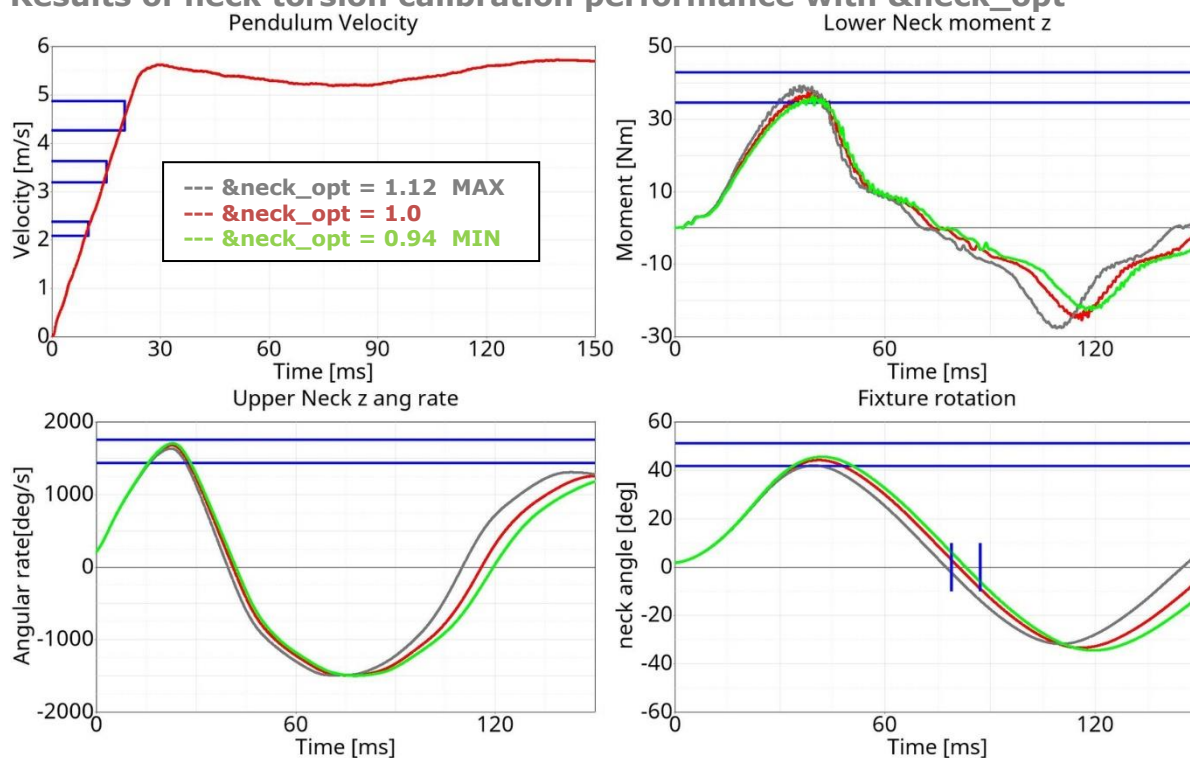


Figure 203: Neck torsion calibration performance

8.2.4 Shoulder pendulum test

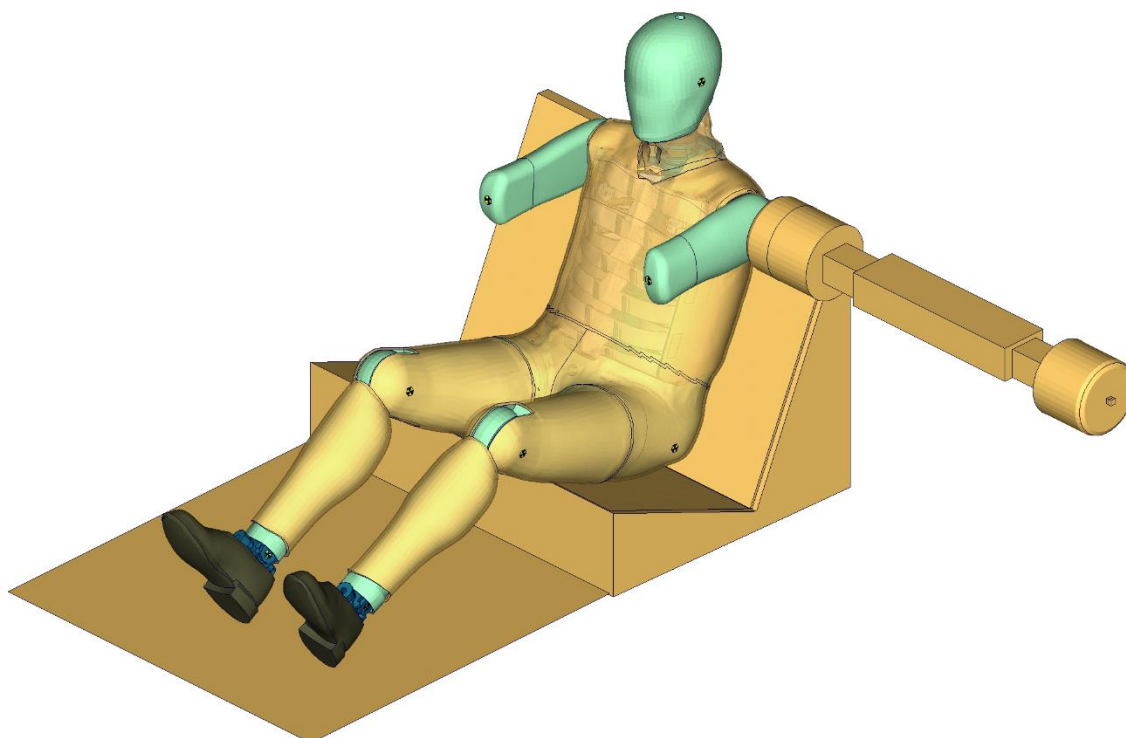


Figure 204: Shoulder calibration test setup

Results of shoulder calibration test with arm (Page 1)

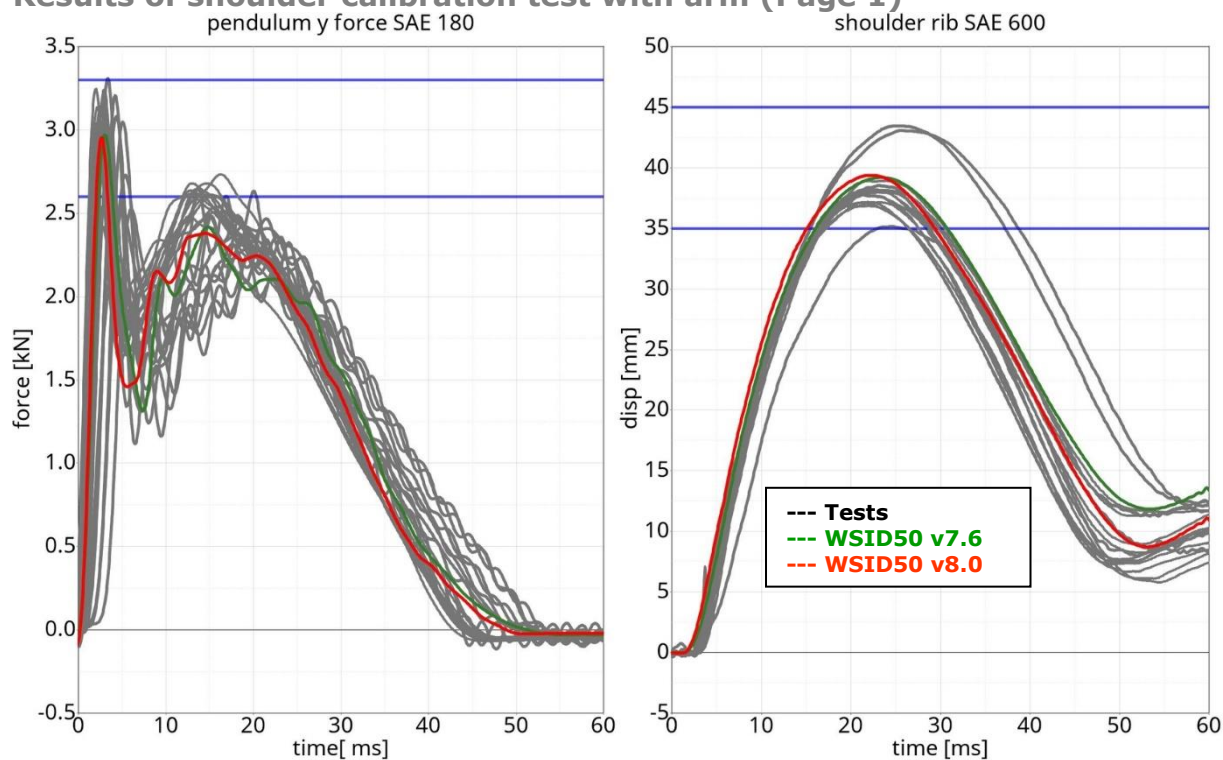


Figure 205: Shoulder calibration test results with arm (Page 1)

Results of shoulder calibration performance with &shd_opt

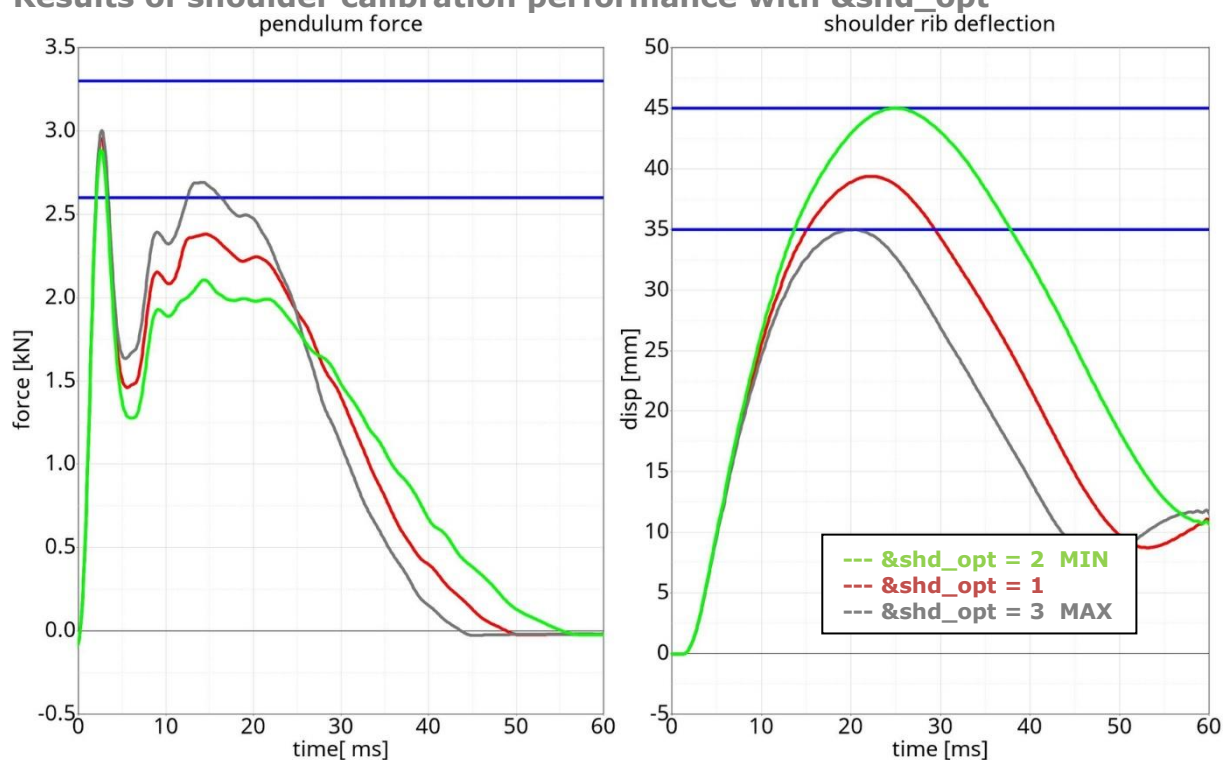


Figure 206: Shoulder calibration performance

8.2.5 Thorax pendulum test

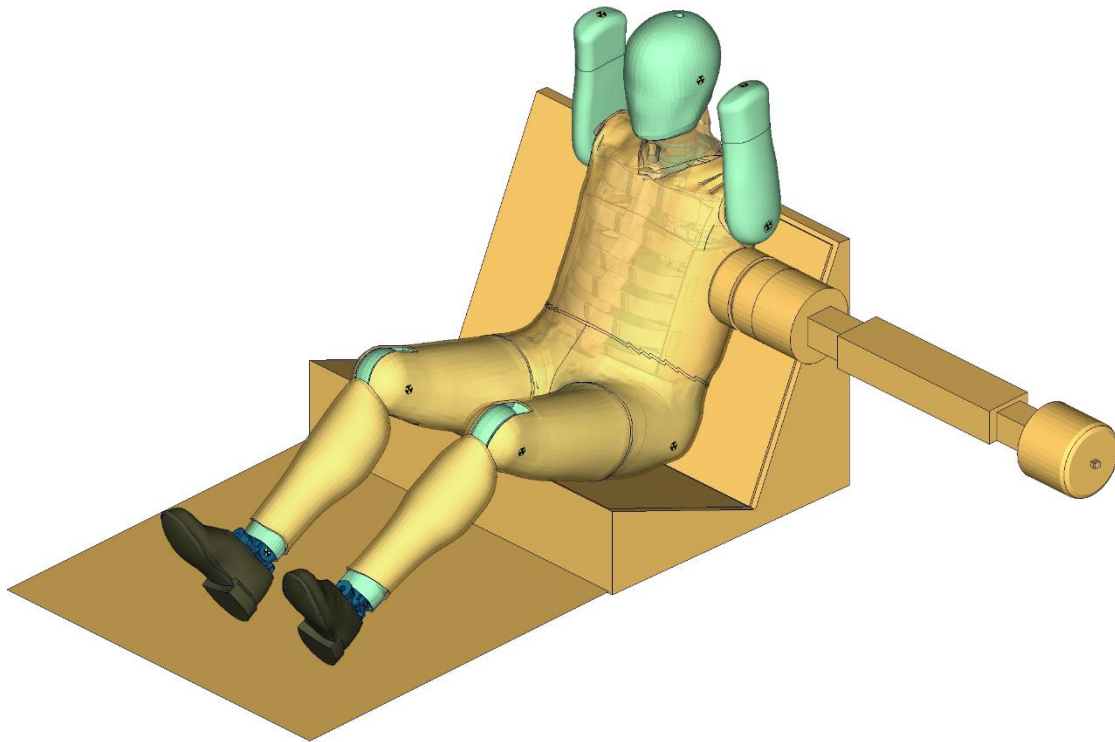


Figure 207: Thorax calibration test setup

Results of thorax calibration test without arm (Page 1)

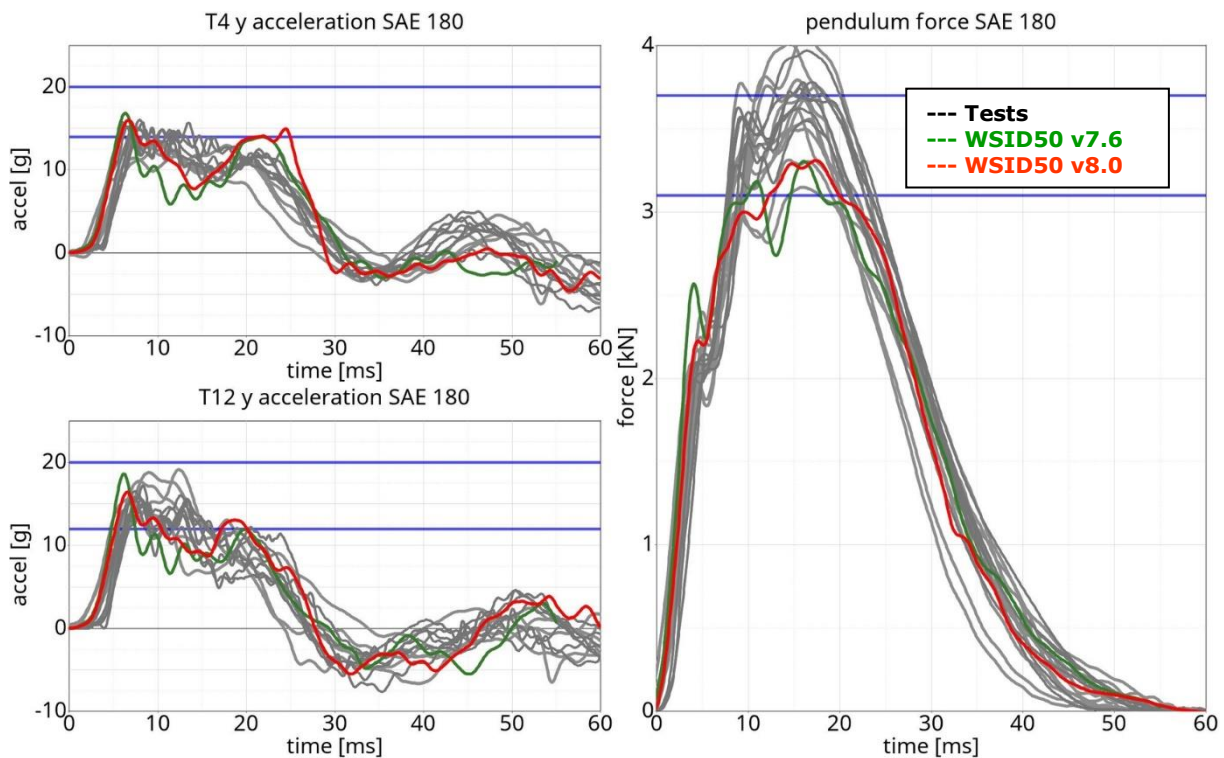


Figure 208: Thorax calibration test results without arm (Page 1)

Results of thorax calibration test without arm (Page 2)

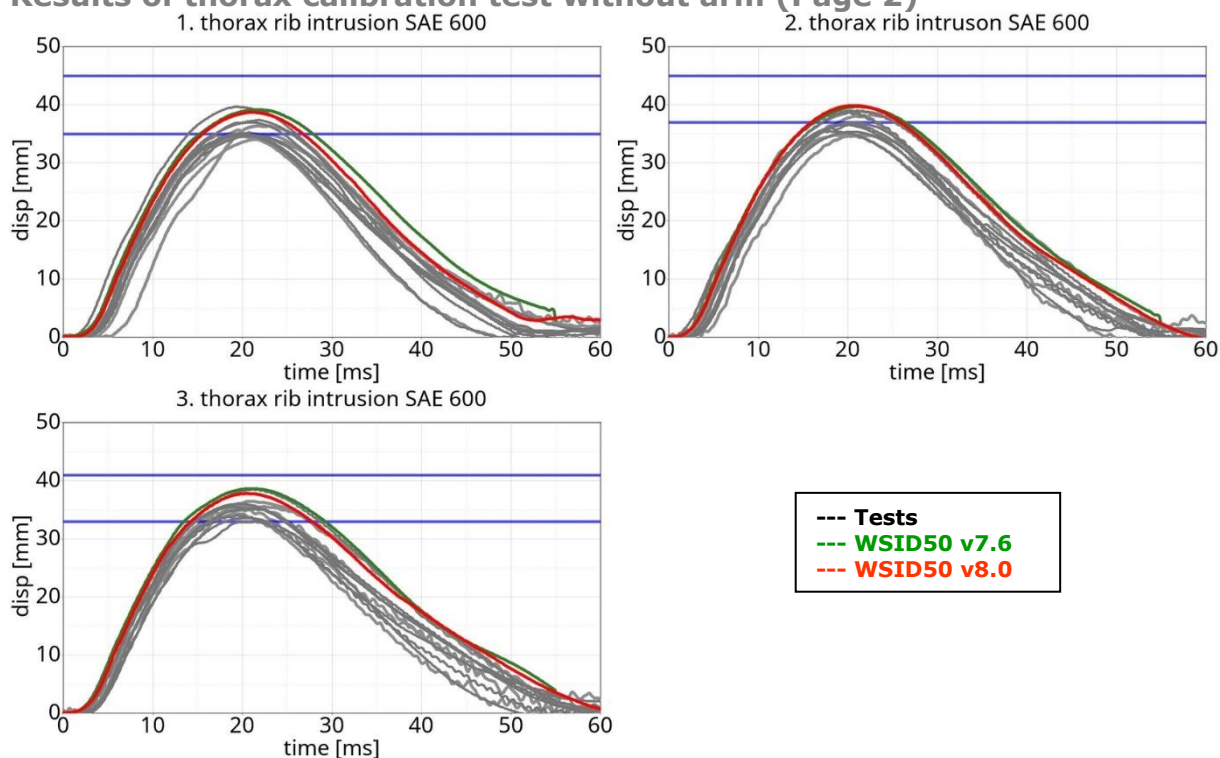


Figure 209: Thorax calibration test results without arm (Page 2)

Results of thorax calibration performance with &trd_opt (Page 1)

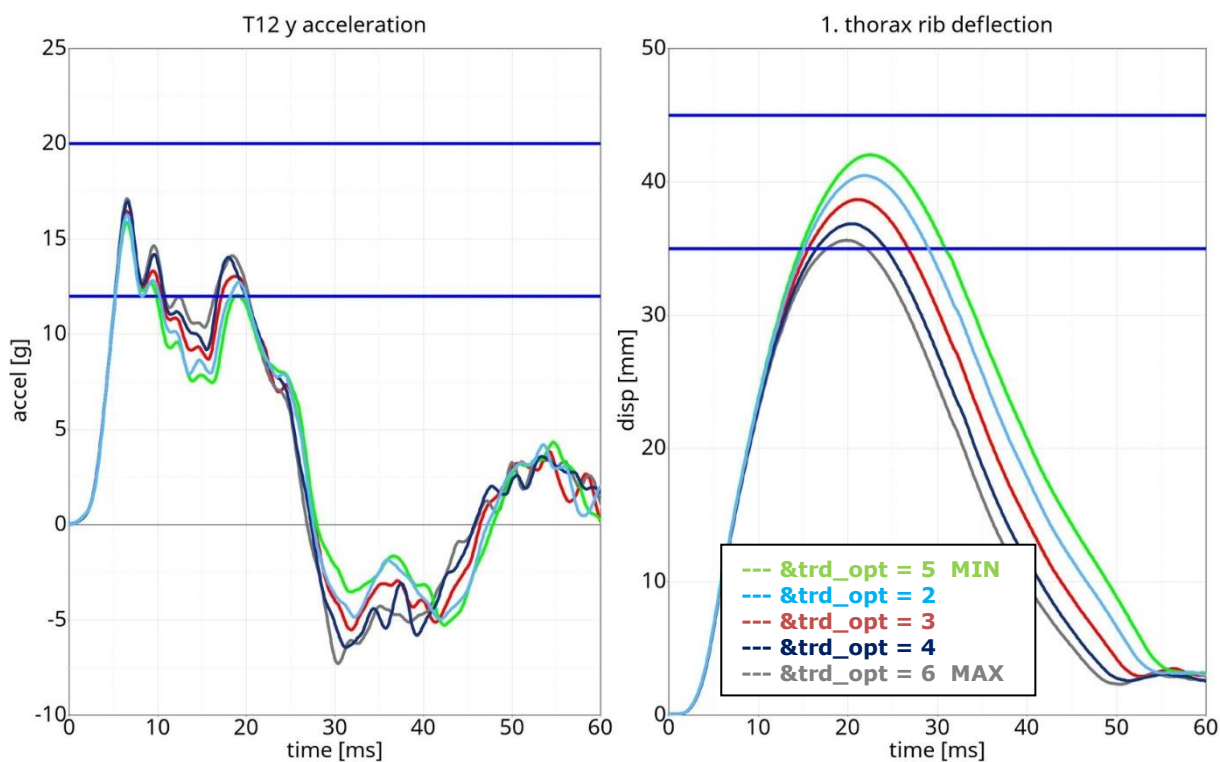


Figure 210: Thorax calibration performance (Page 1)

Results of thorax calibration performance with &trd_opt (Page 2)

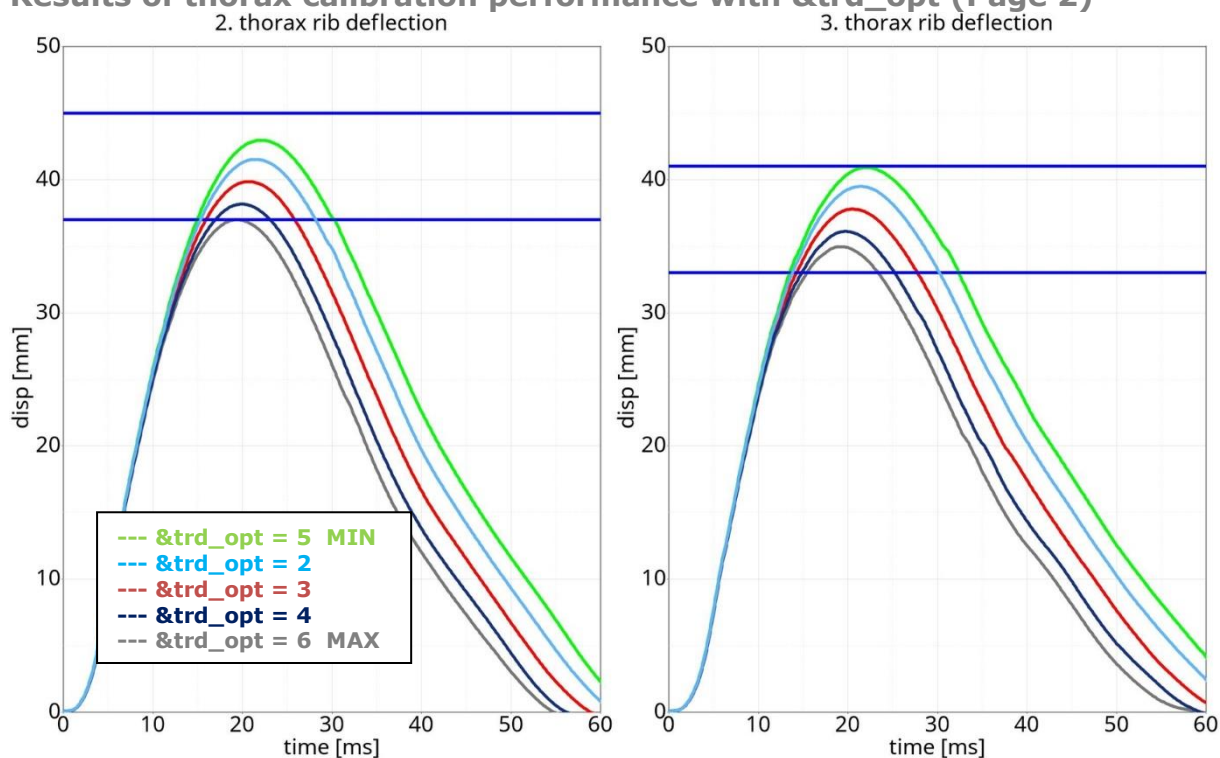


Figure 211: Thorax calibration test results without arm (Page 2)

Results of thorax calibration performance with &trd_opt (Page 3)

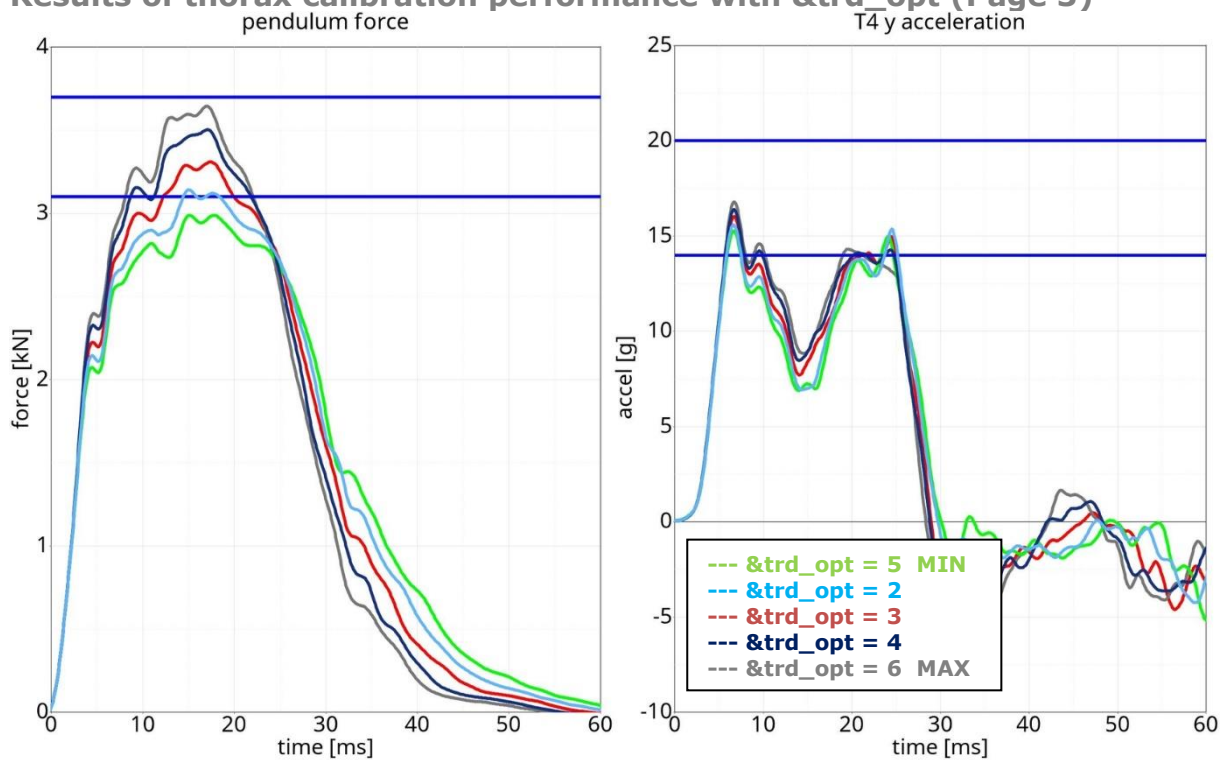


Figure 212: Thorax calibration test results without arm (Page 3)

8.2.6 Abdomen pendulum test

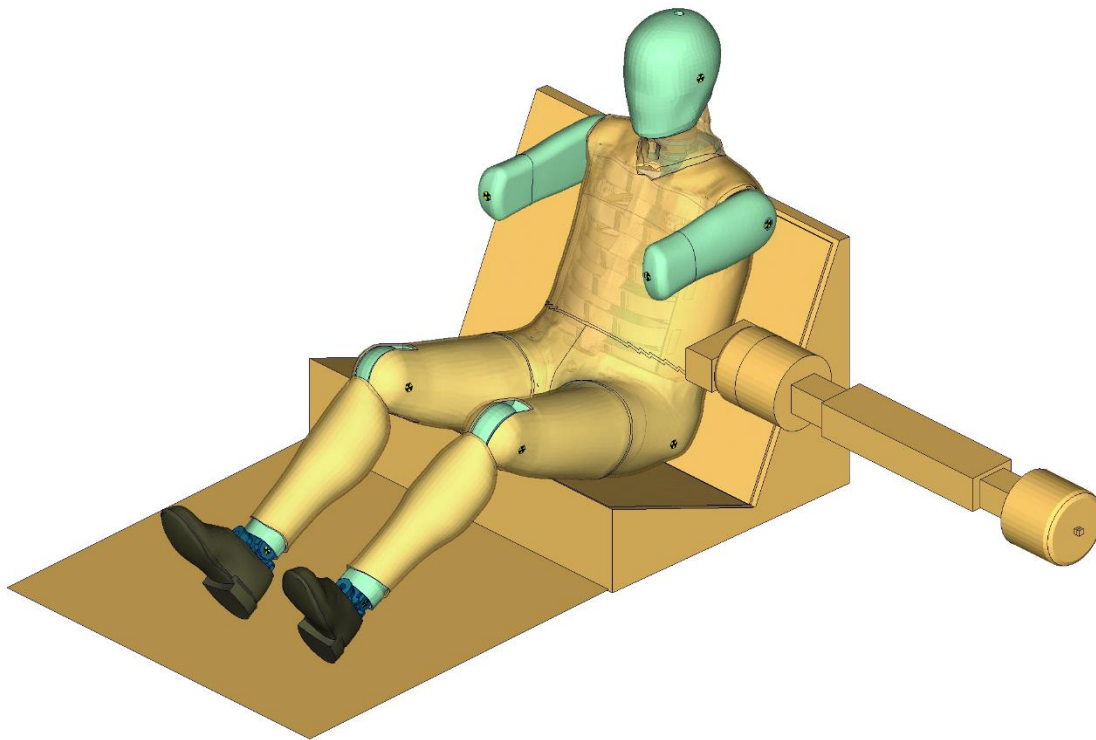


Figure 213: Abdomen calibration test setup

Results of abdomen calibration test with arm (Page 1)

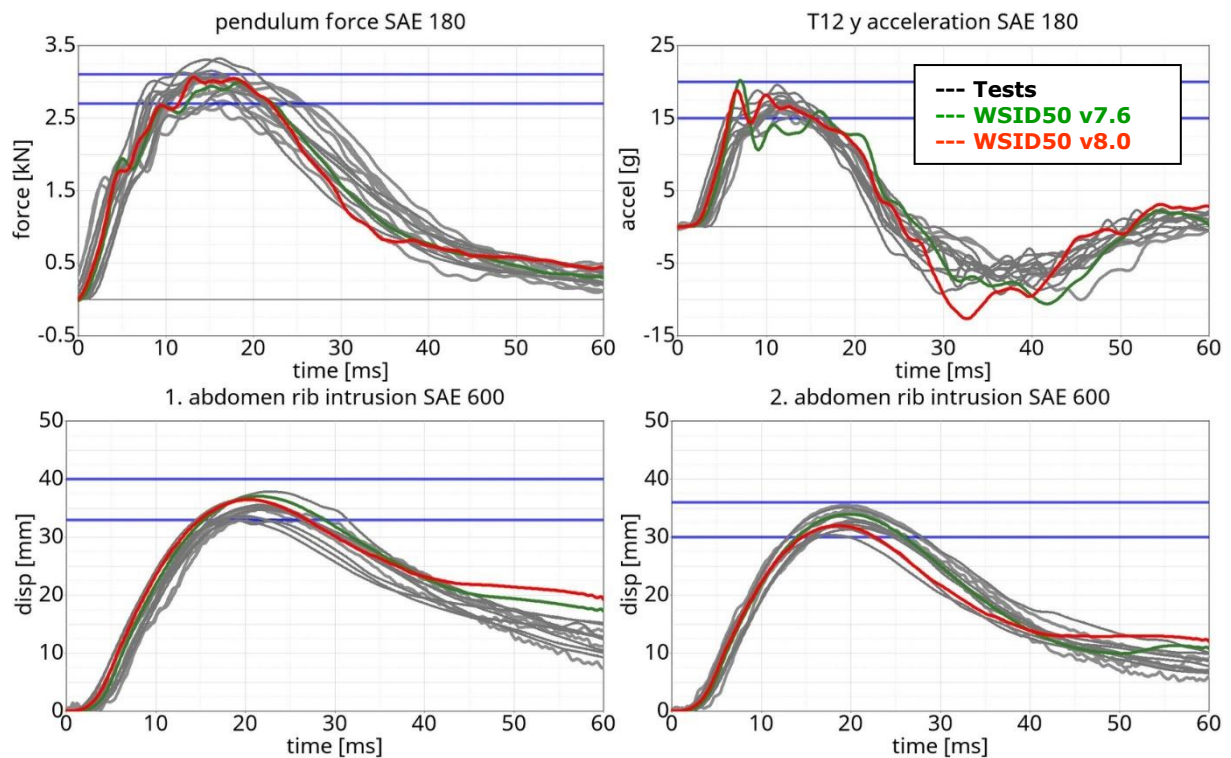


Figure 214: Abdomen calibration test results with arm (Page 1)

Results of abdomen calibration performance with &abd_opt (Page 1)

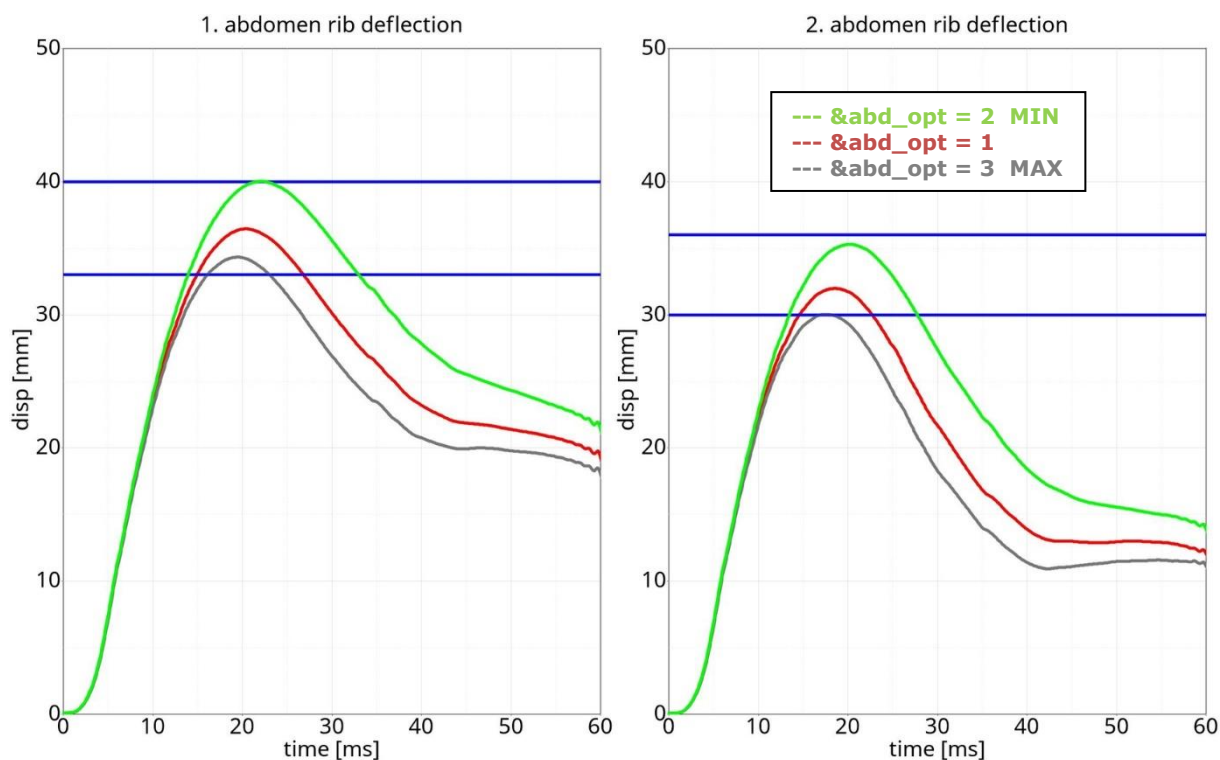


Figure 215: Abdomen calibration performance (Page 1)

Results of abdomen calibration performance with &abd_opt (Page 2)

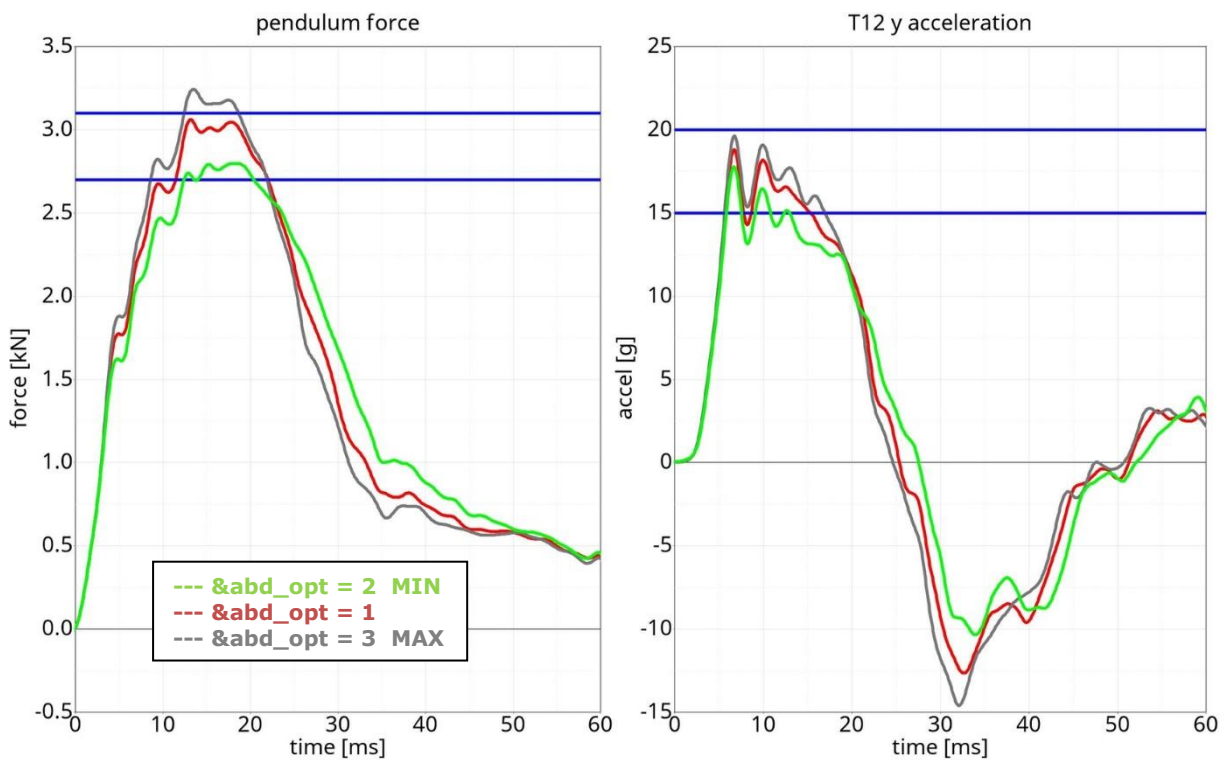


Figure 216: Abdomen calibration performance (Page 2)

8.2.7 Pelvis pendulum test

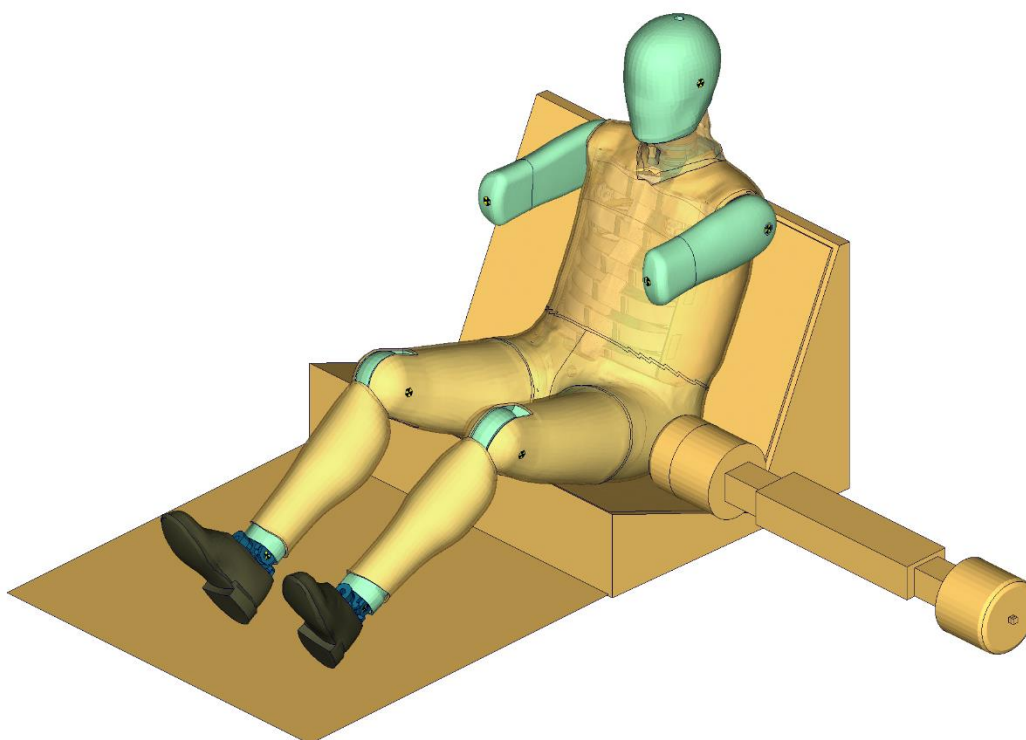


Figure 217: Pelvis calibration test setup

Results of pelvis calibration test with arm (Page 1)

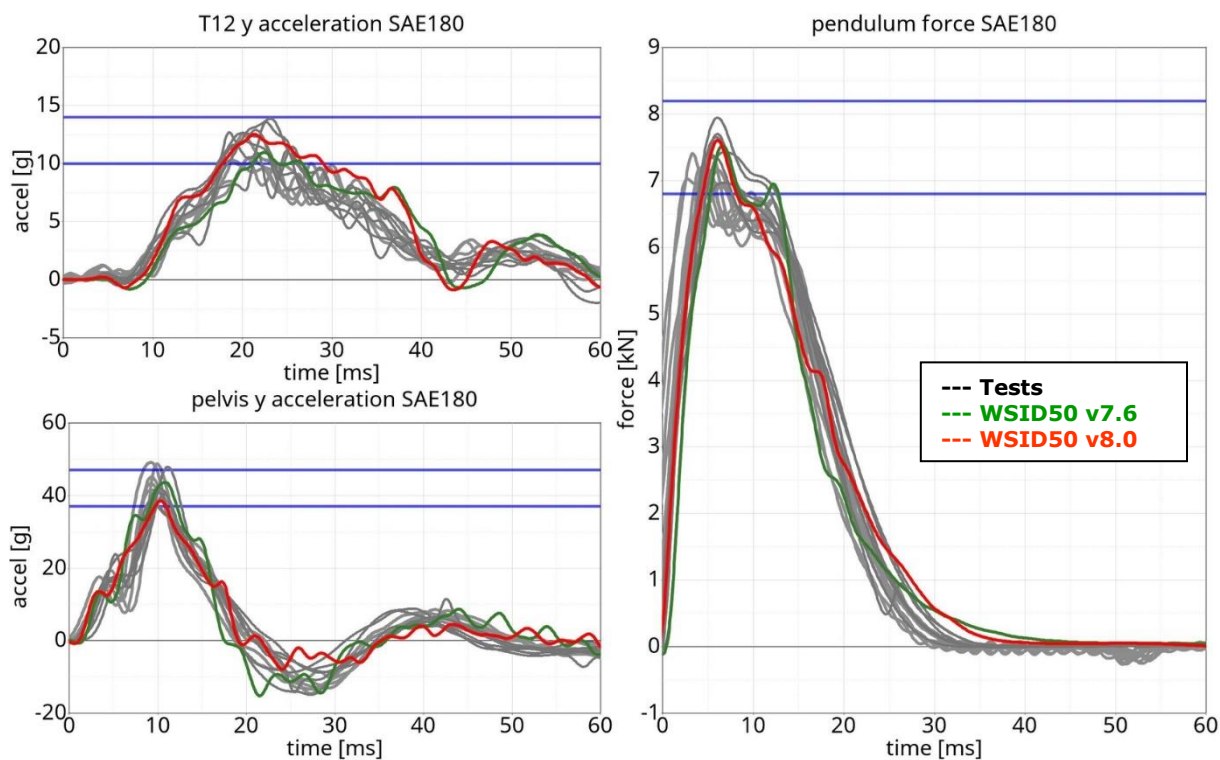
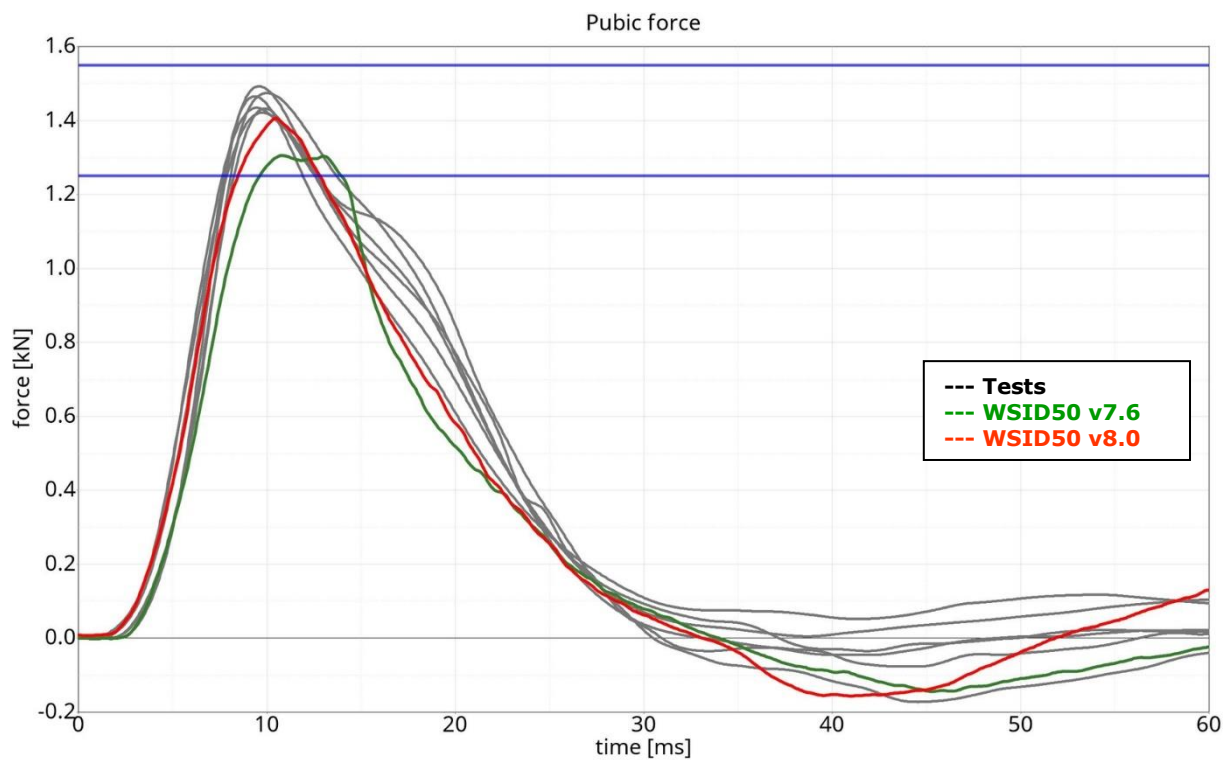
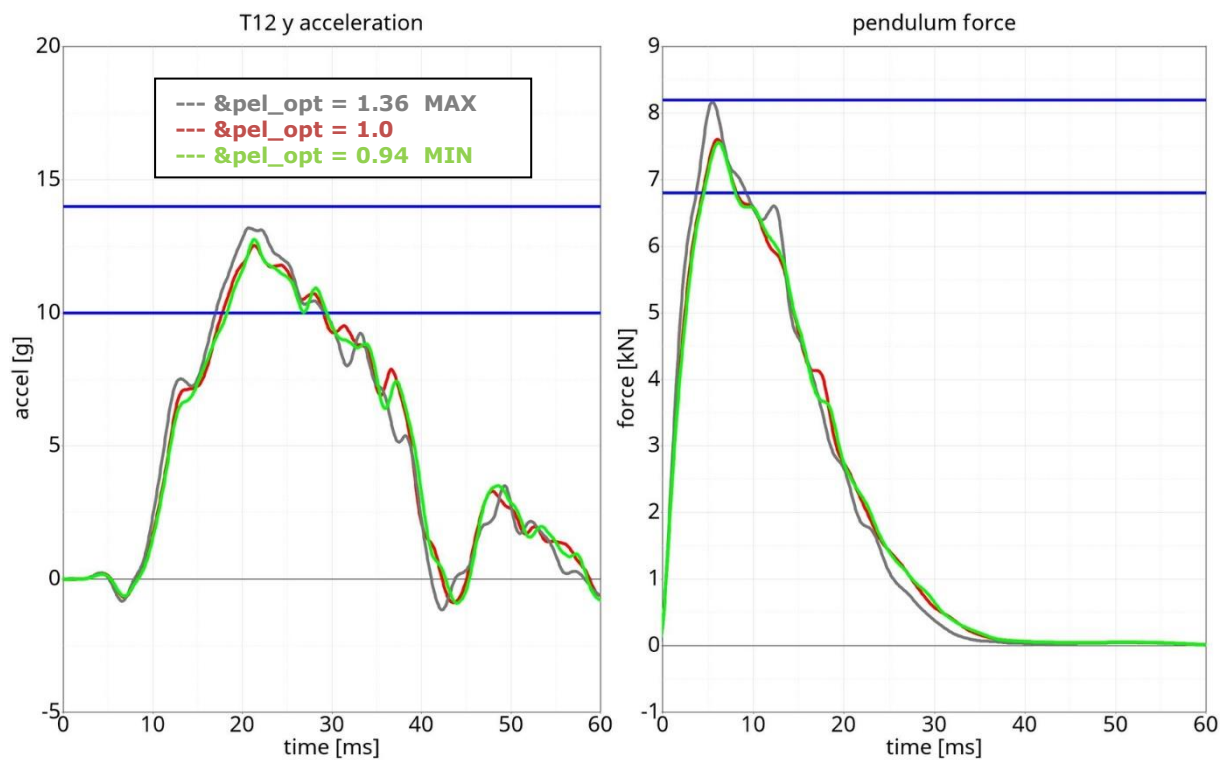


Figure 218: Pelvis calibration test results with arm (Page 1)

Results of pelvis calibration test with arm (Page 2)**Figure 219:** Pelvis calibration test results with arm (Page 2)**Results of pelvis calibration performance with &pel_opt (Page 1)****Figure 220:** Pelvis calibration performance (Page 1)

Results of pelvis calibration performance with &pel_opt (Page 2)

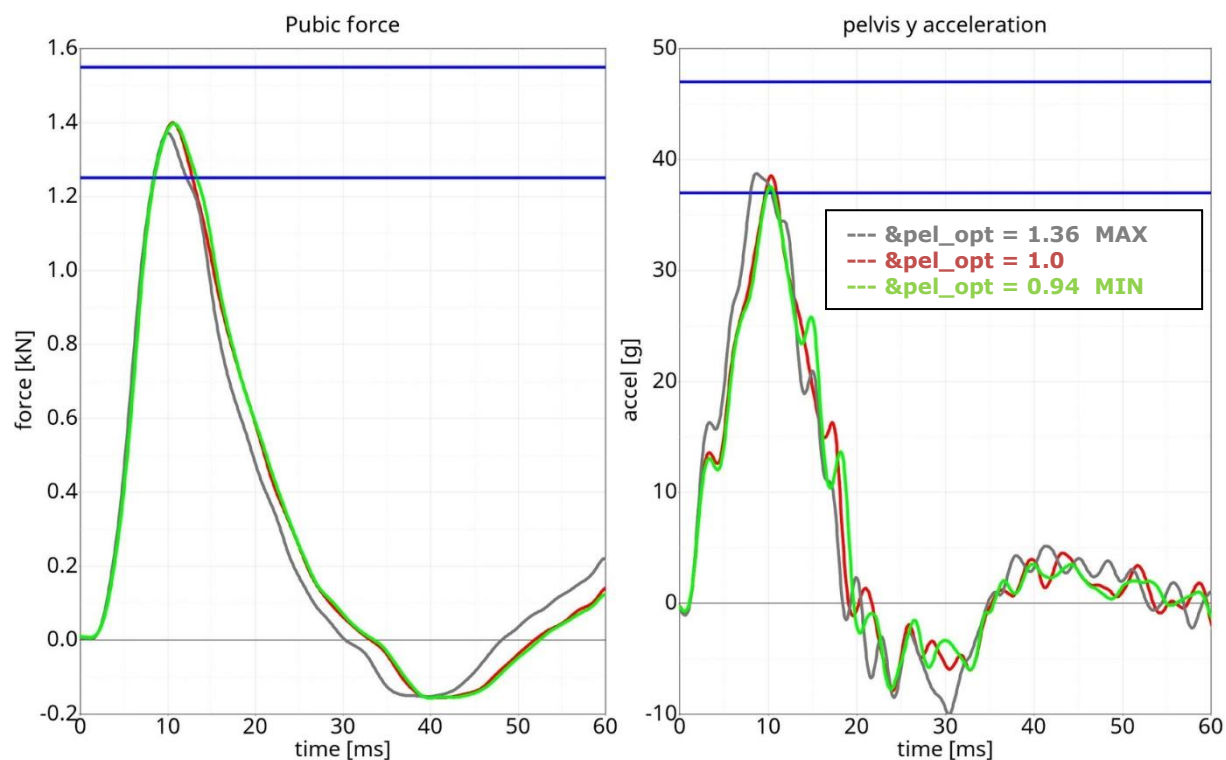


Figure 221: Pelvis calibration performance (Page 2)

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.

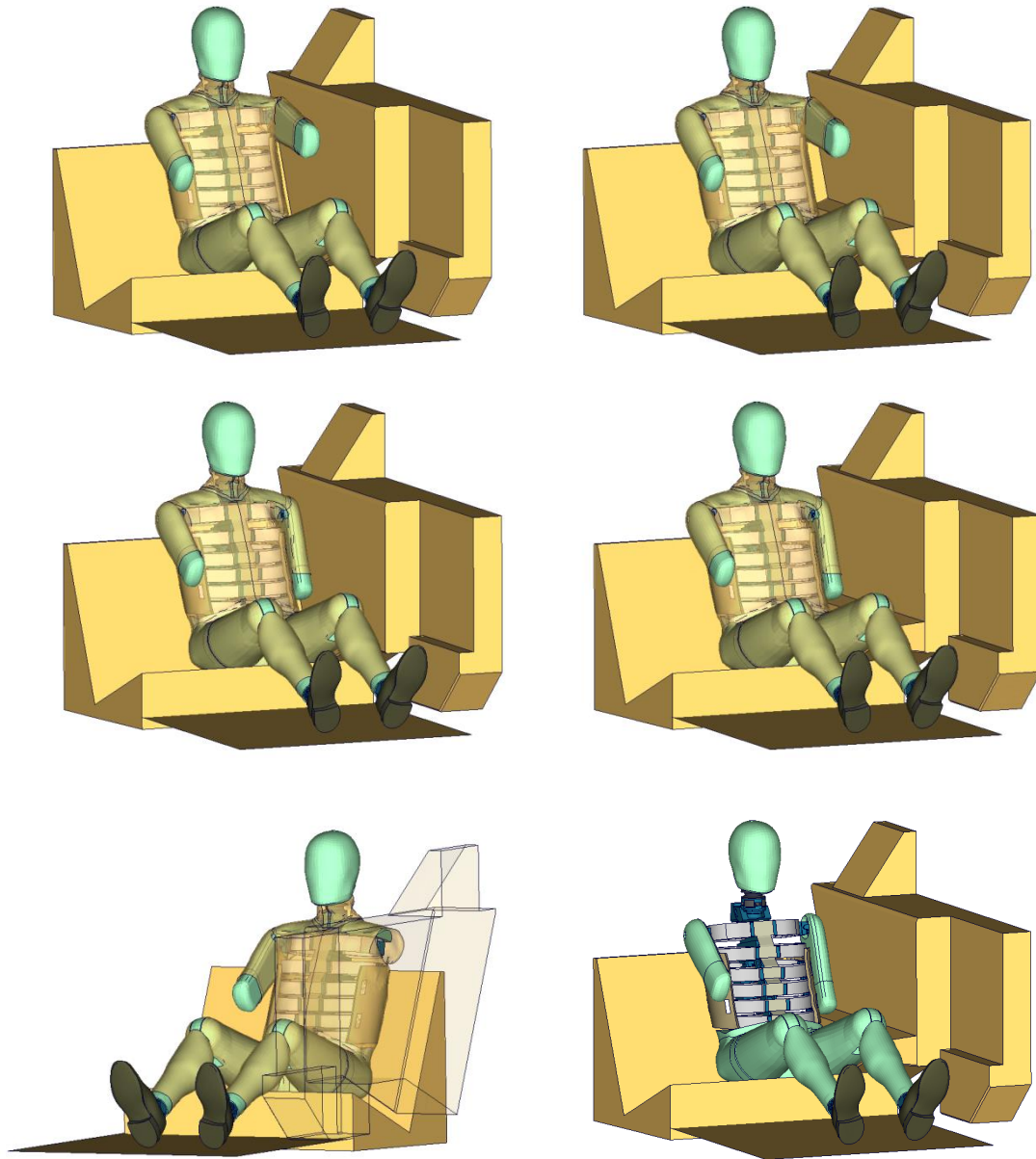


Figure 222: Sled tests for next WorldSID release. Left hand side: Plane sled.
Right hand side: Plane sled with pelvis pusher

8.3.1 Flat barrier

8.3.1.1 Arm position second notch

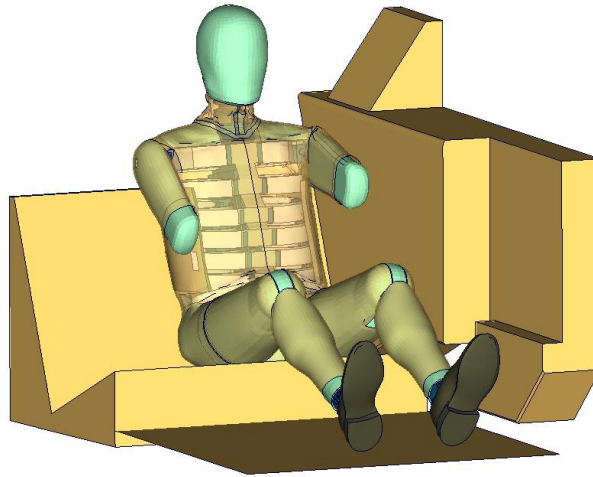
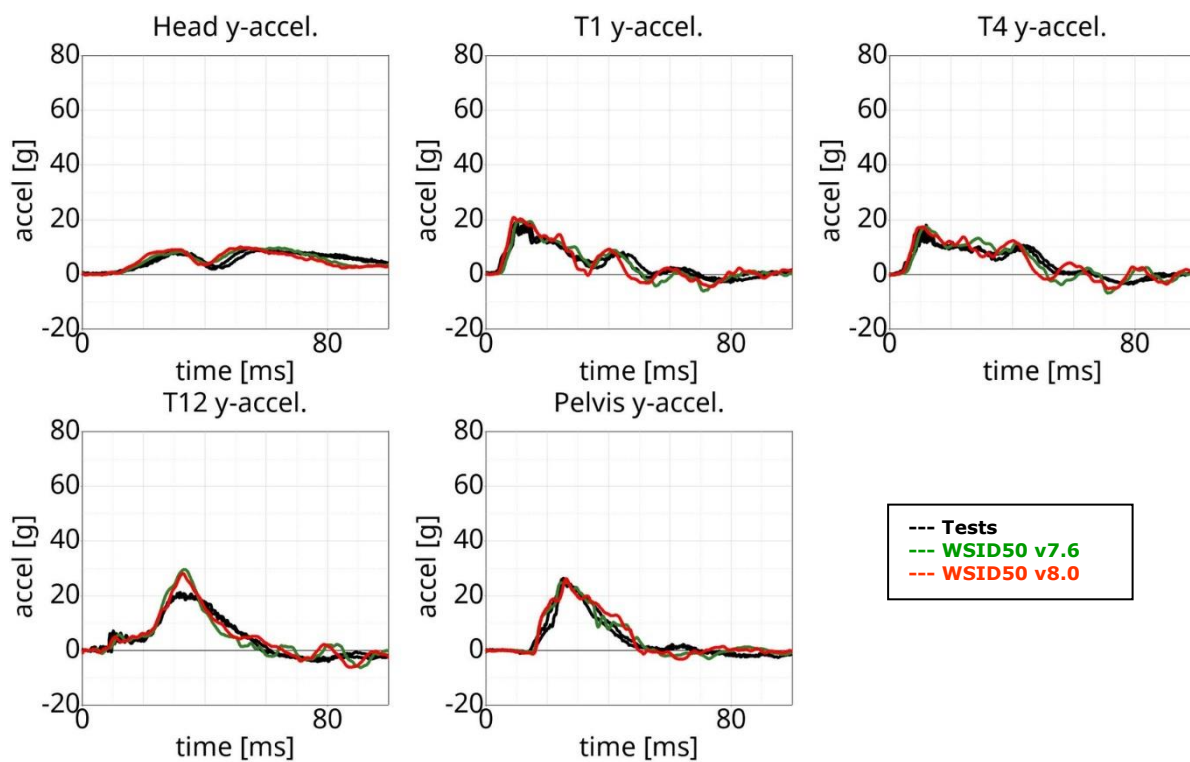
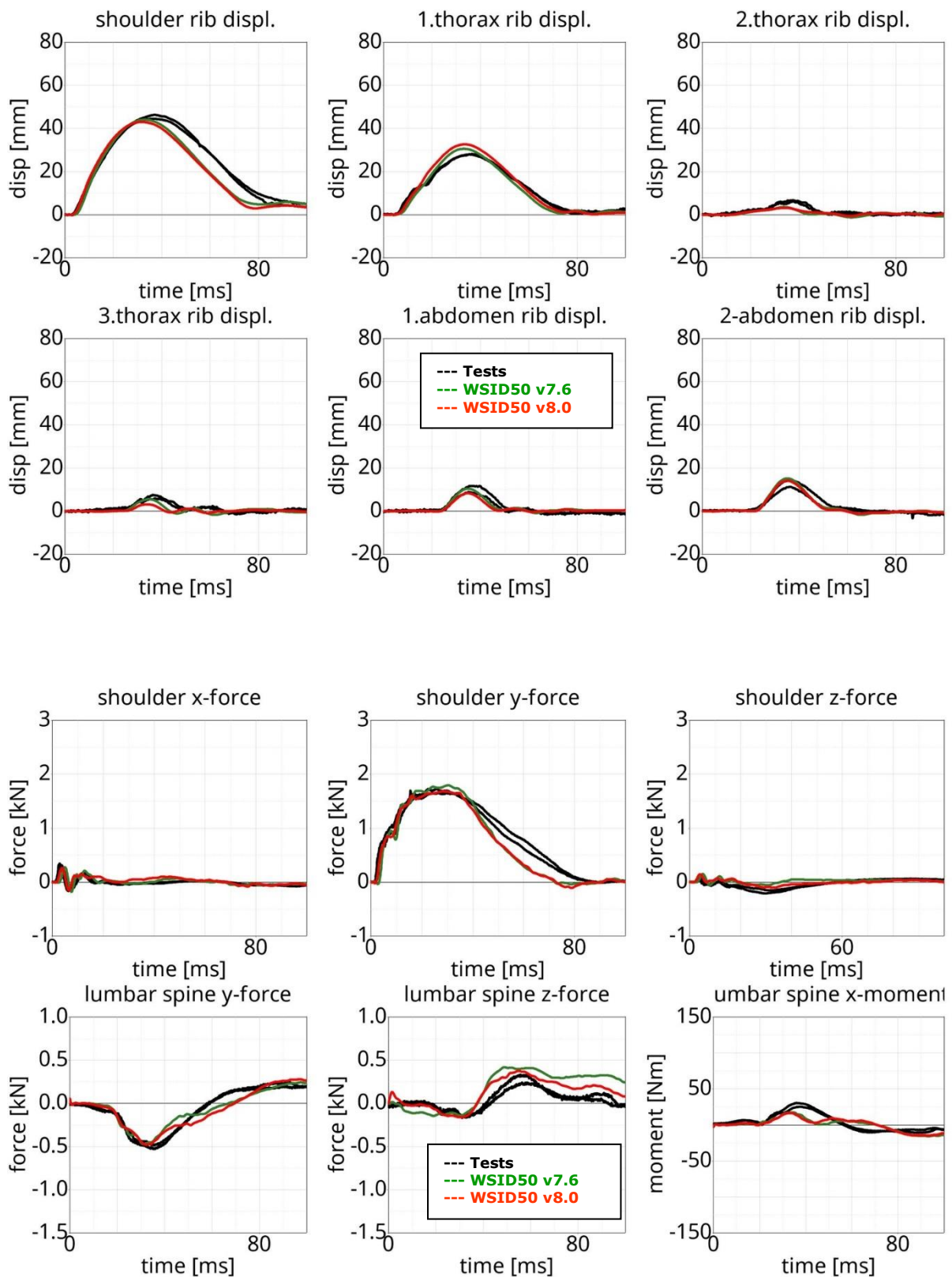


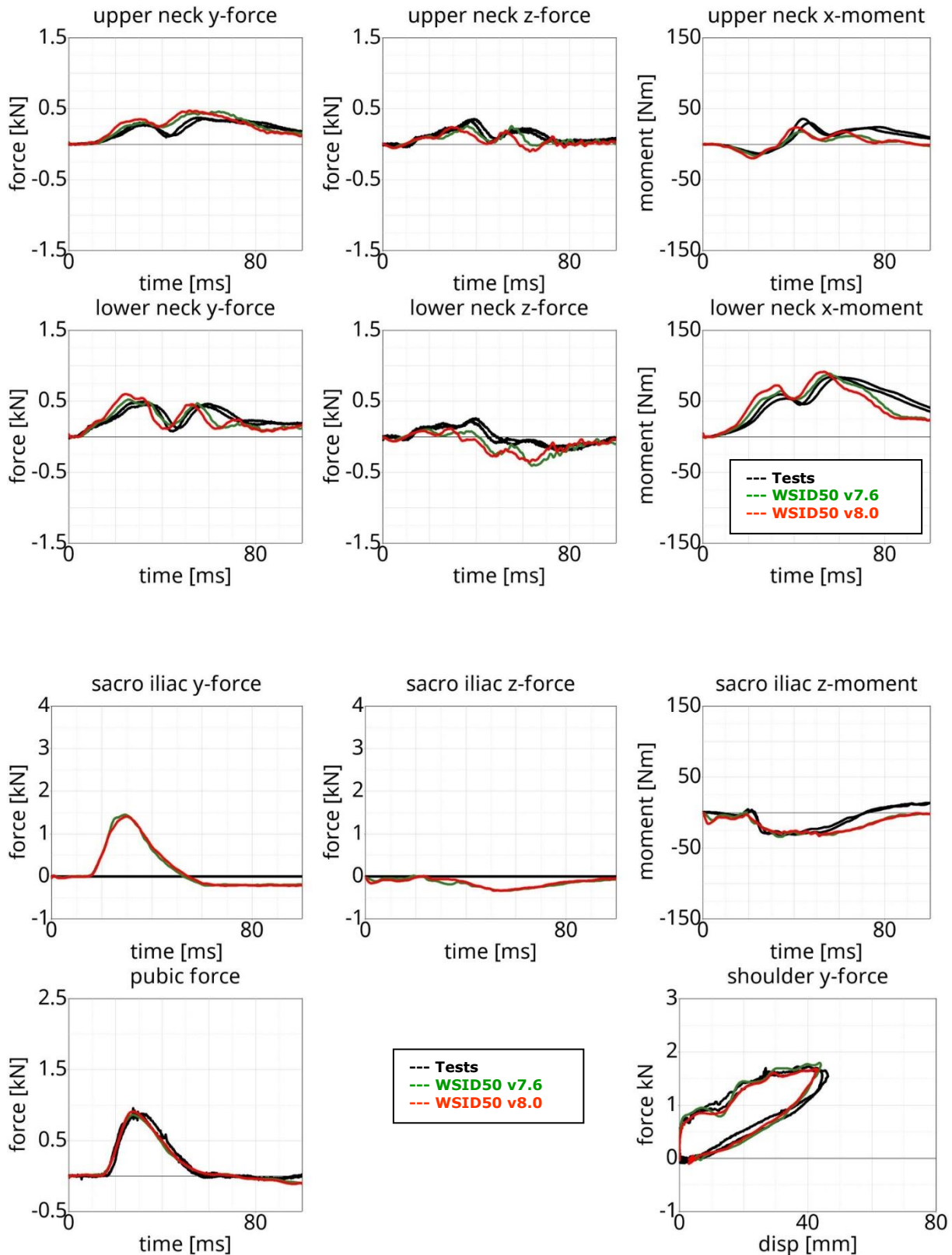
Figure 223: Flat barrier and arm second notch.

Low velocity:

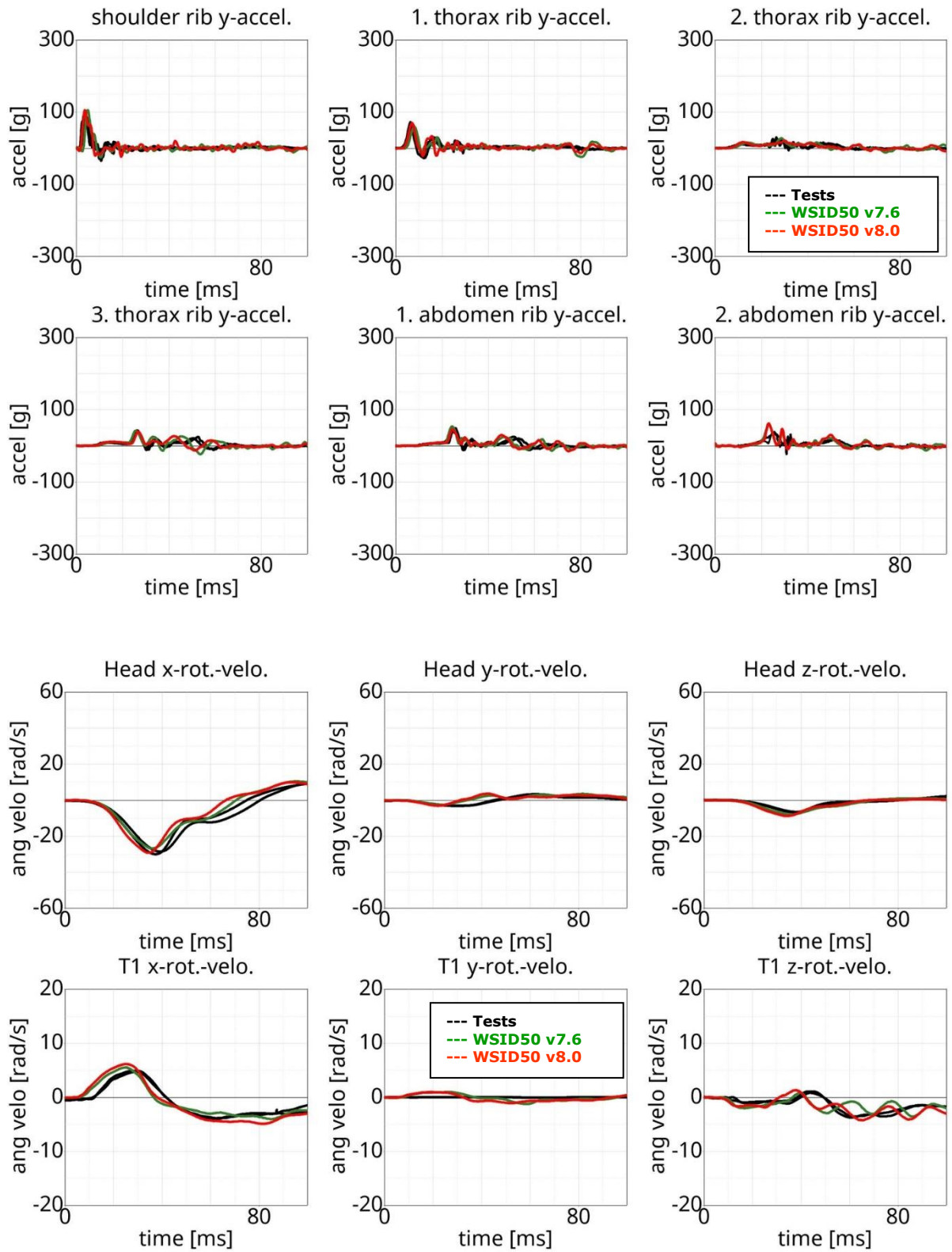




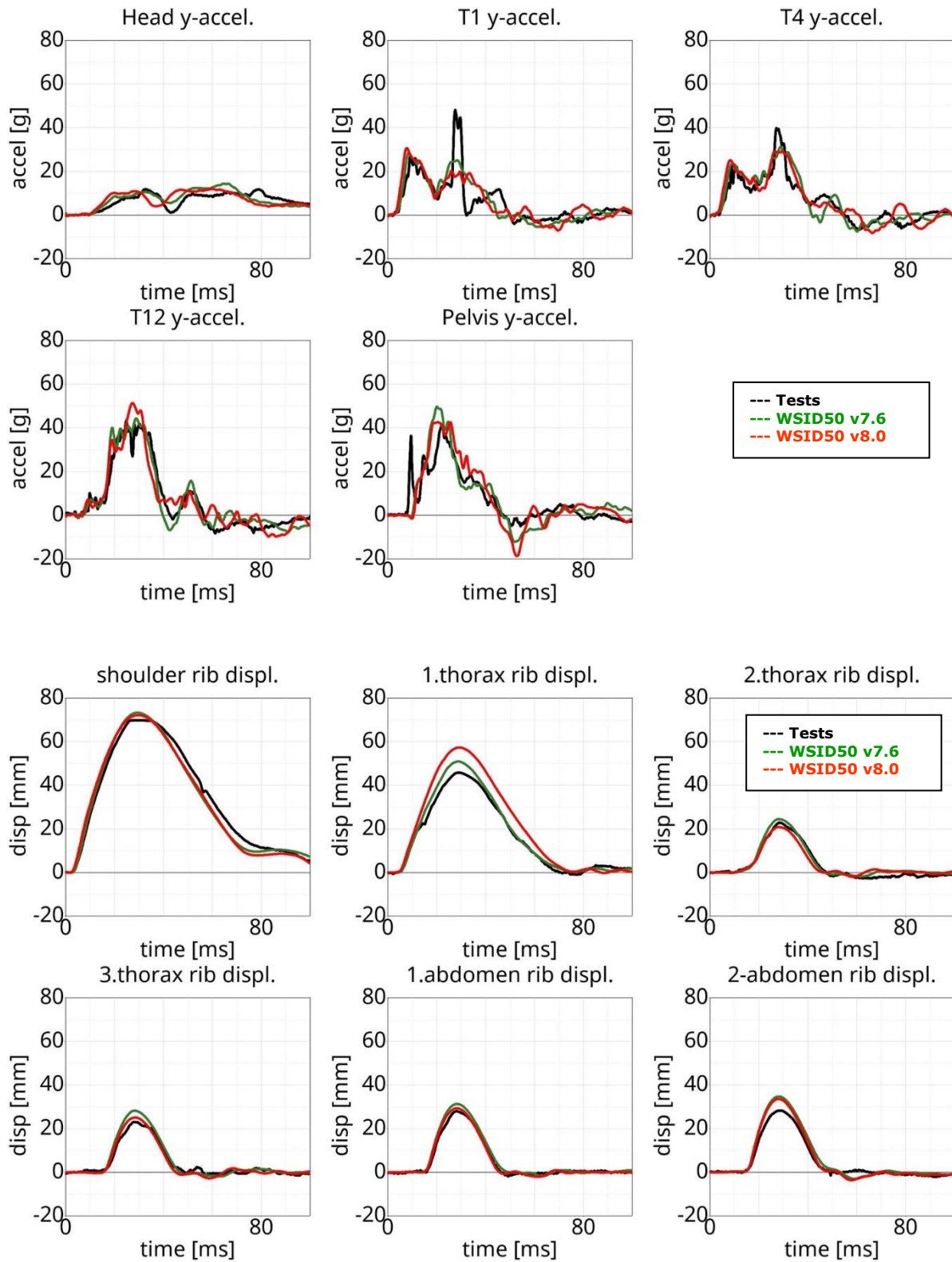
Performance – sled tests



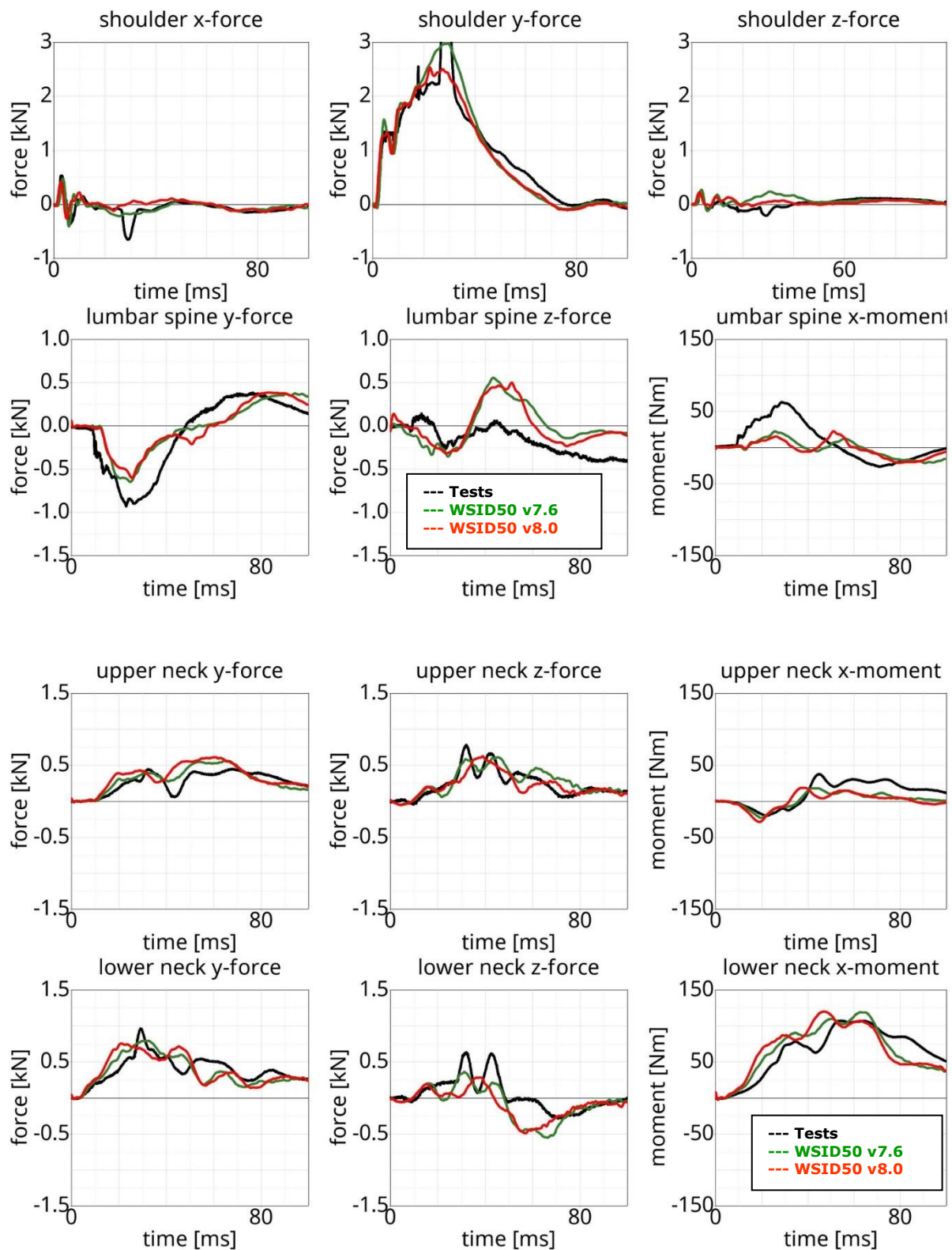
Performance – sled tests



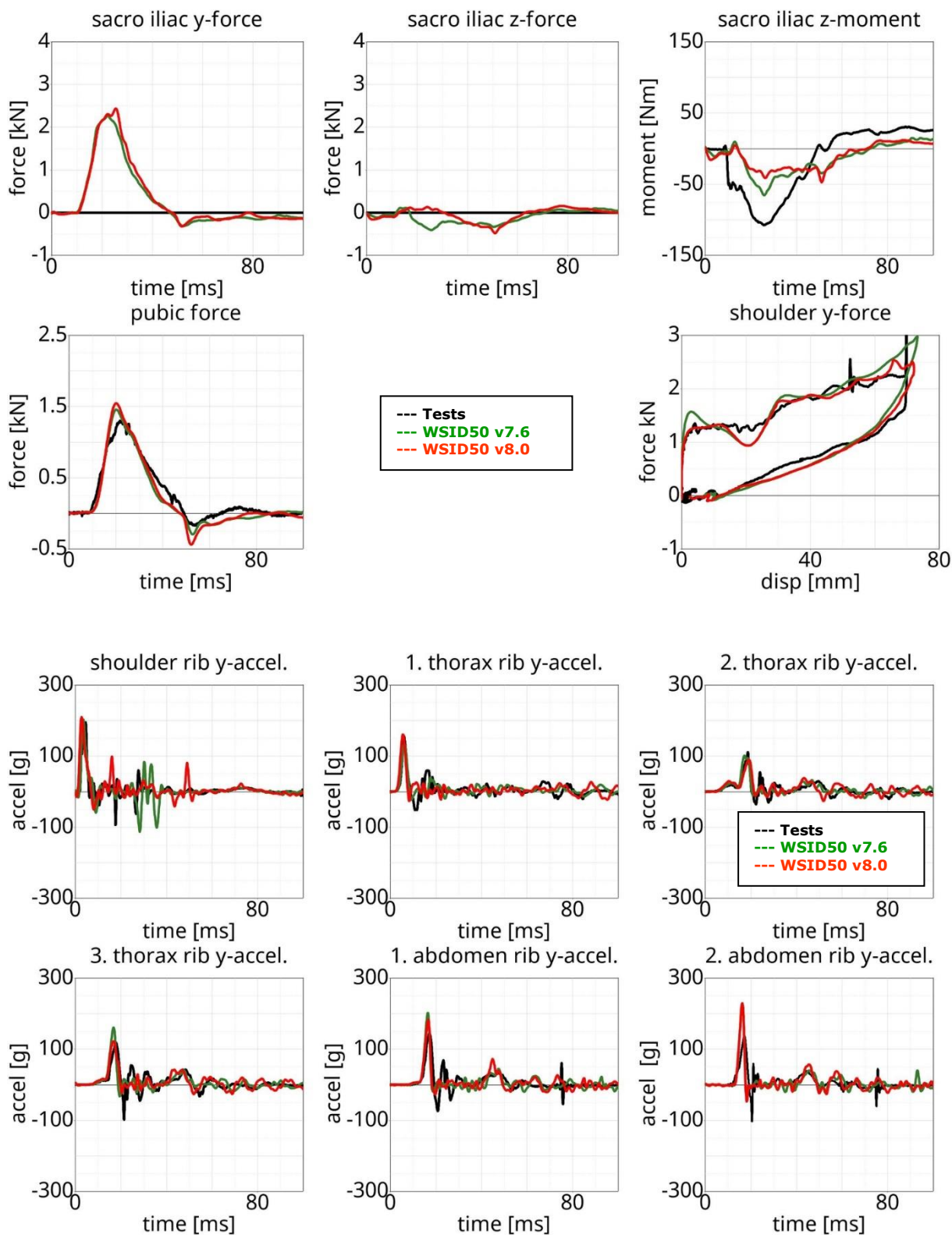
High velocity:



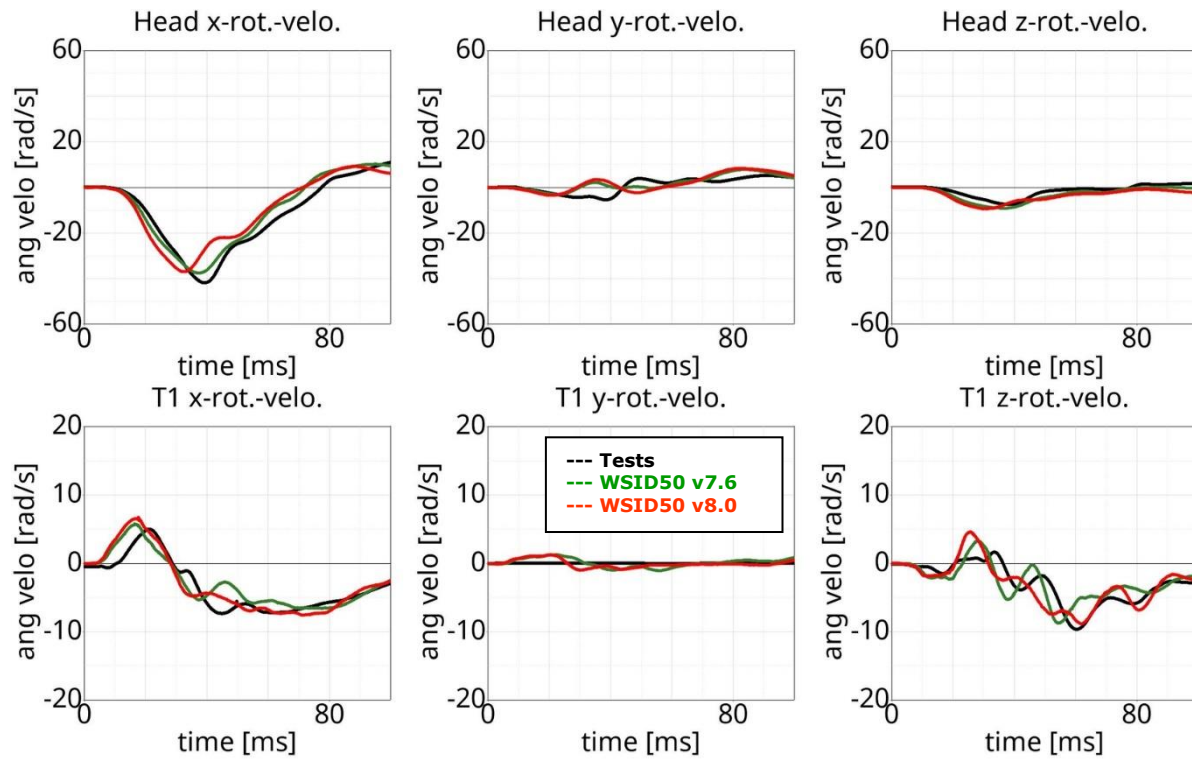
Performance – sled tests



Performance – sled tests



Performance – sled tests



8.3.1.2 Arm position first notch

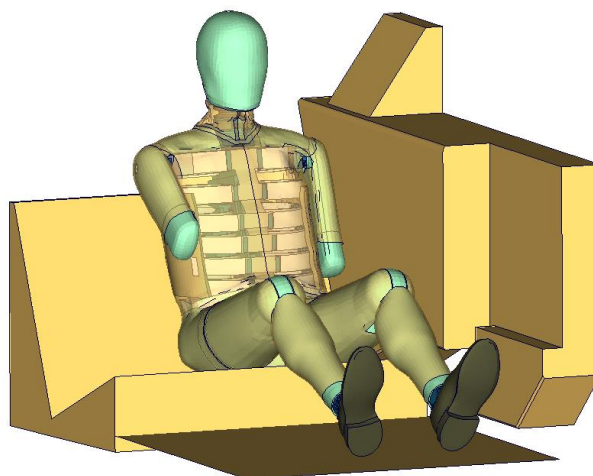
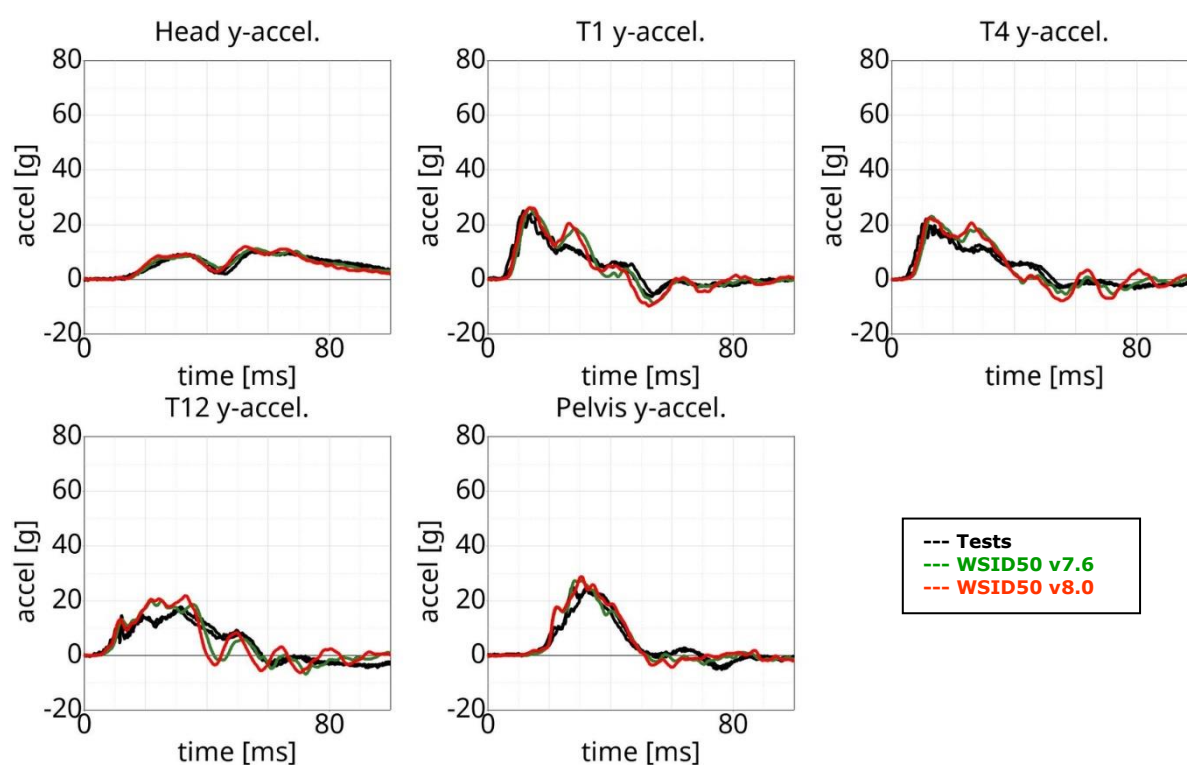
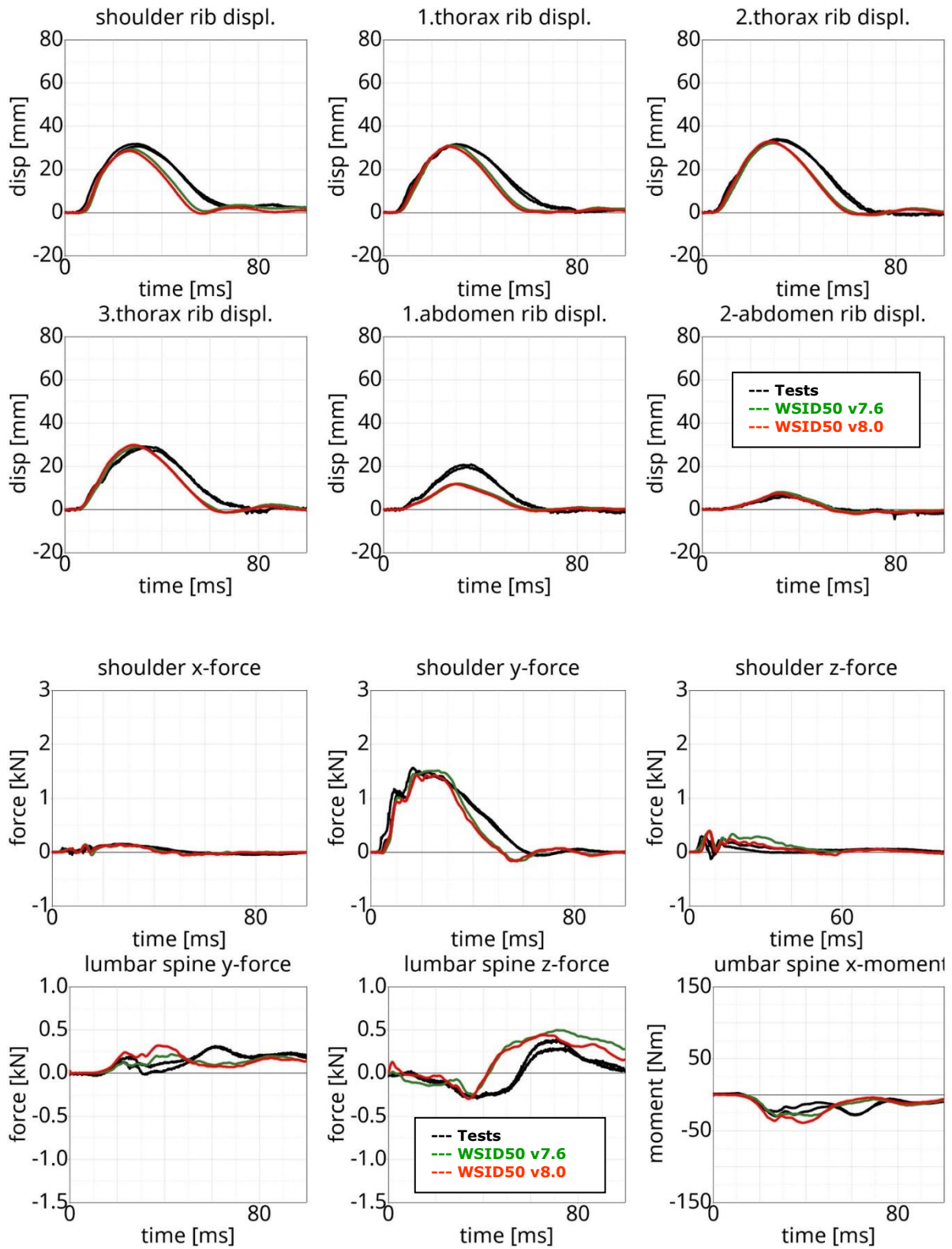


Figure 224: Flat barrier and arm first notch.

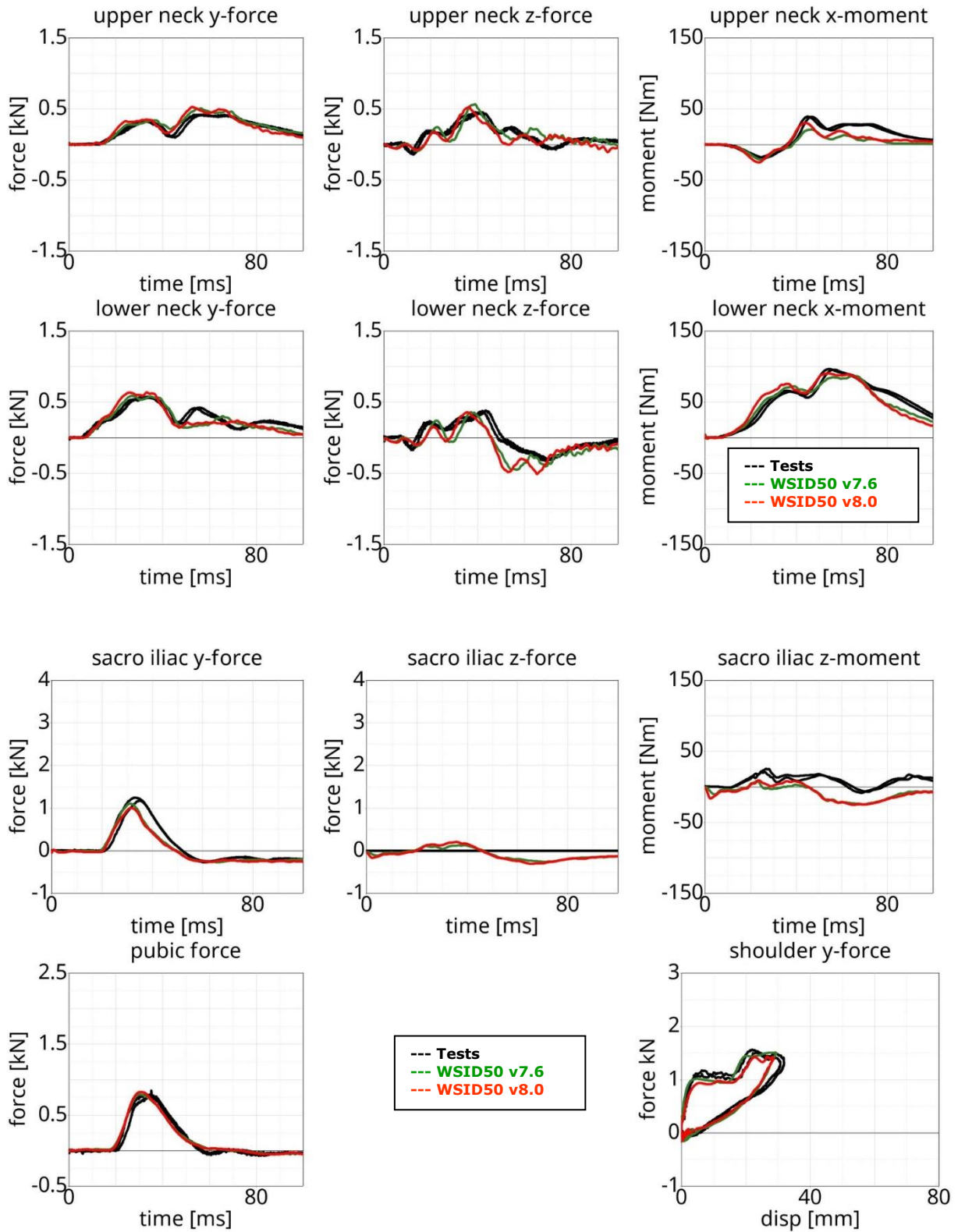
Low velocities:

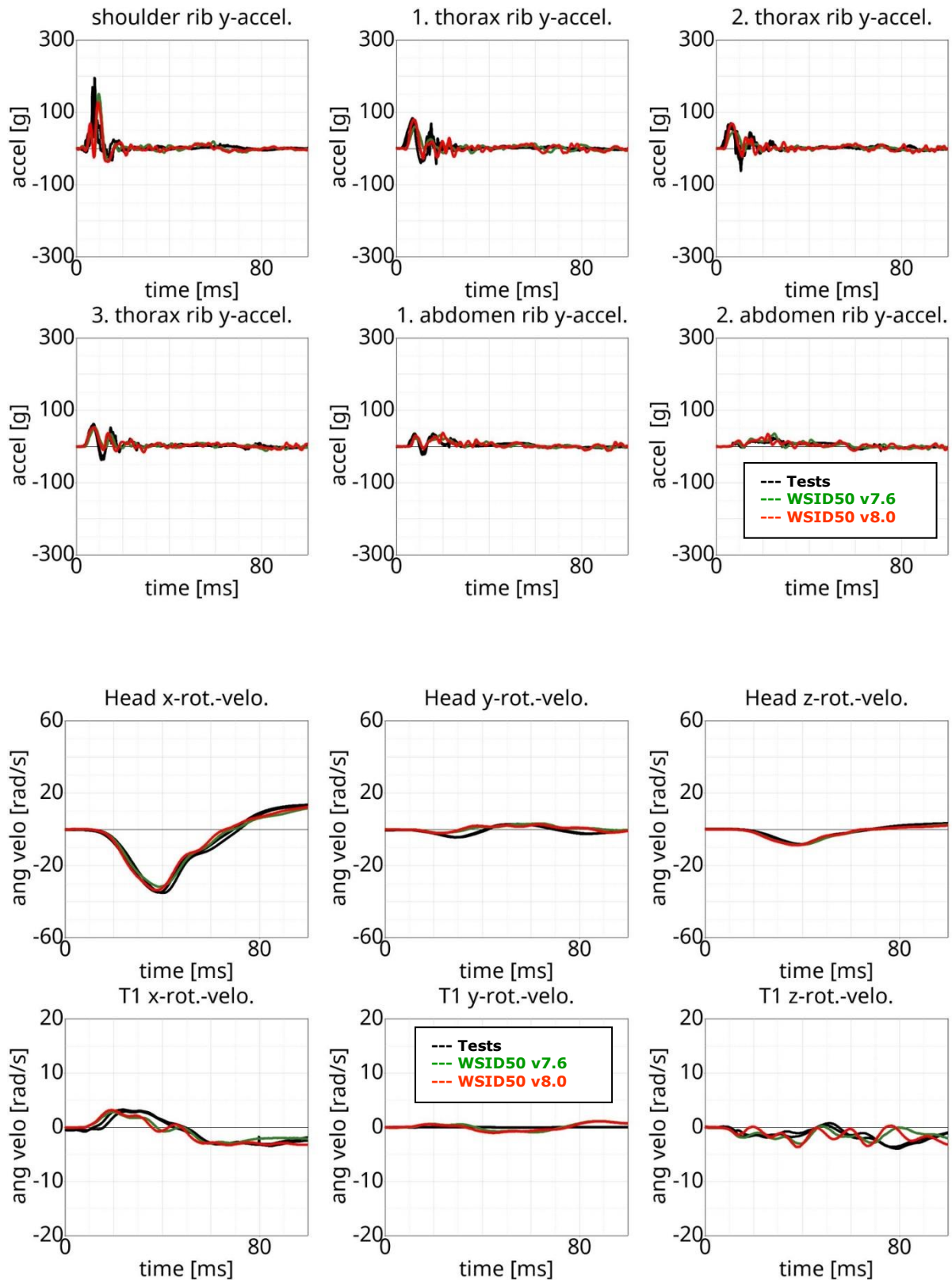


Performance – sled tests

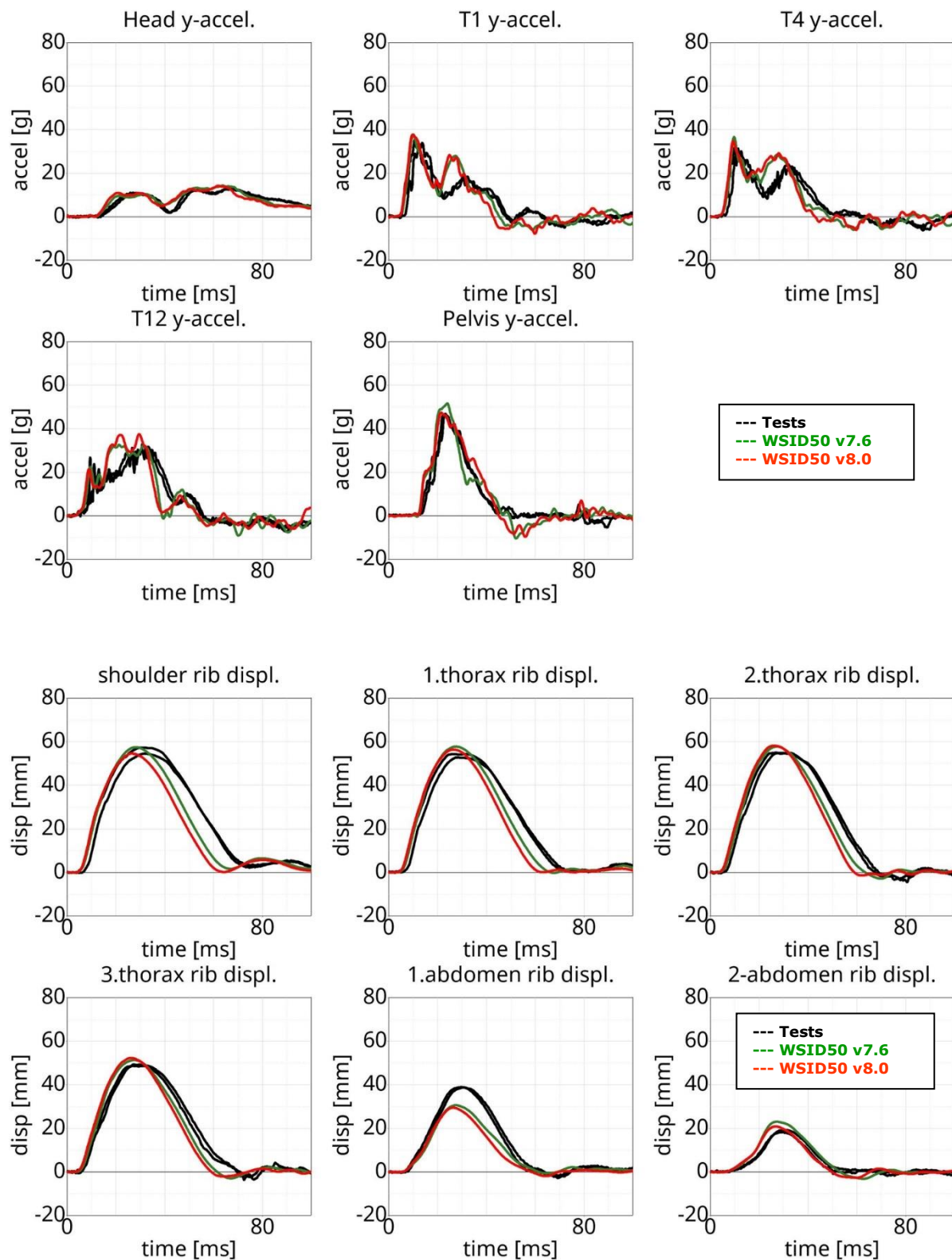


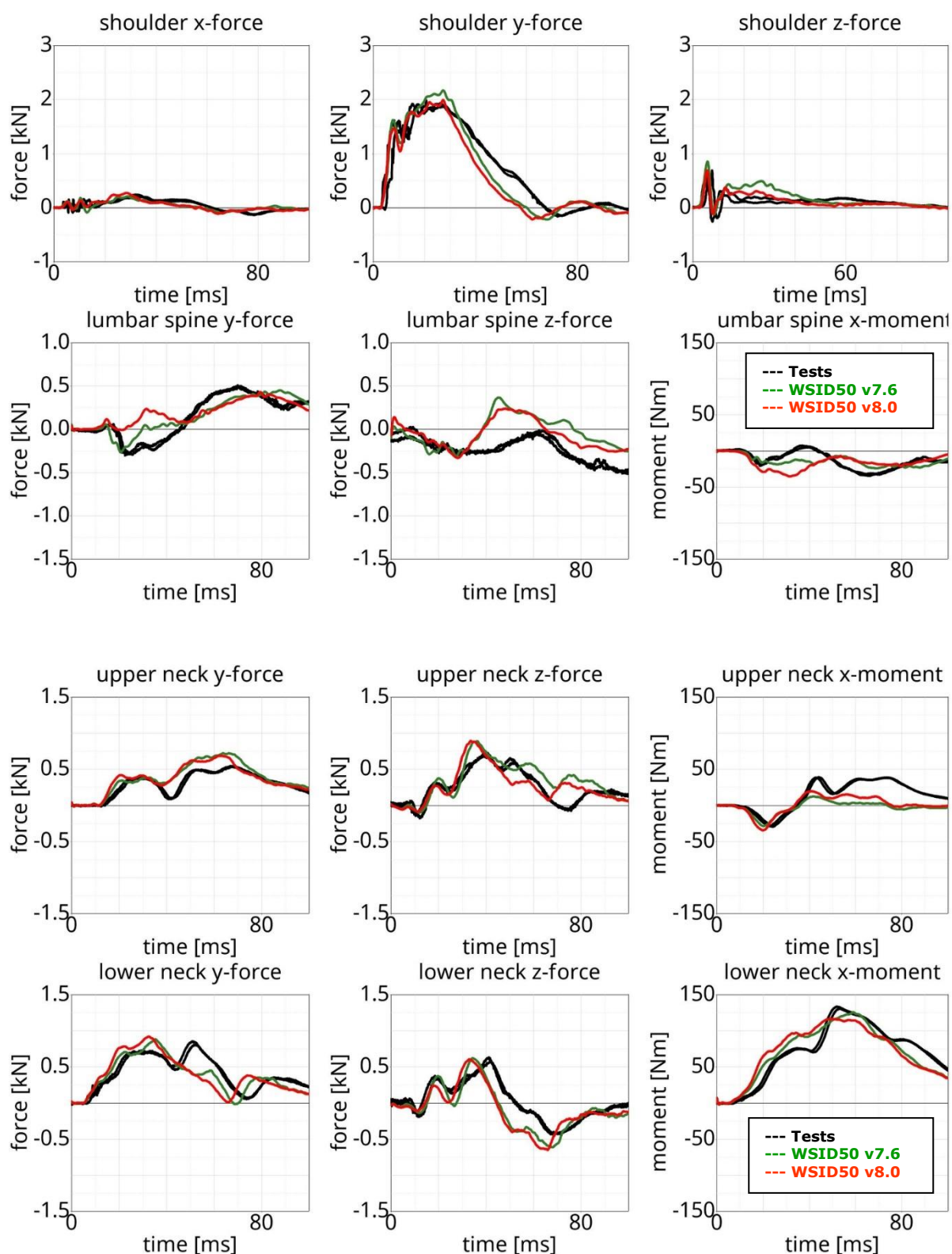
Performance – sled tests



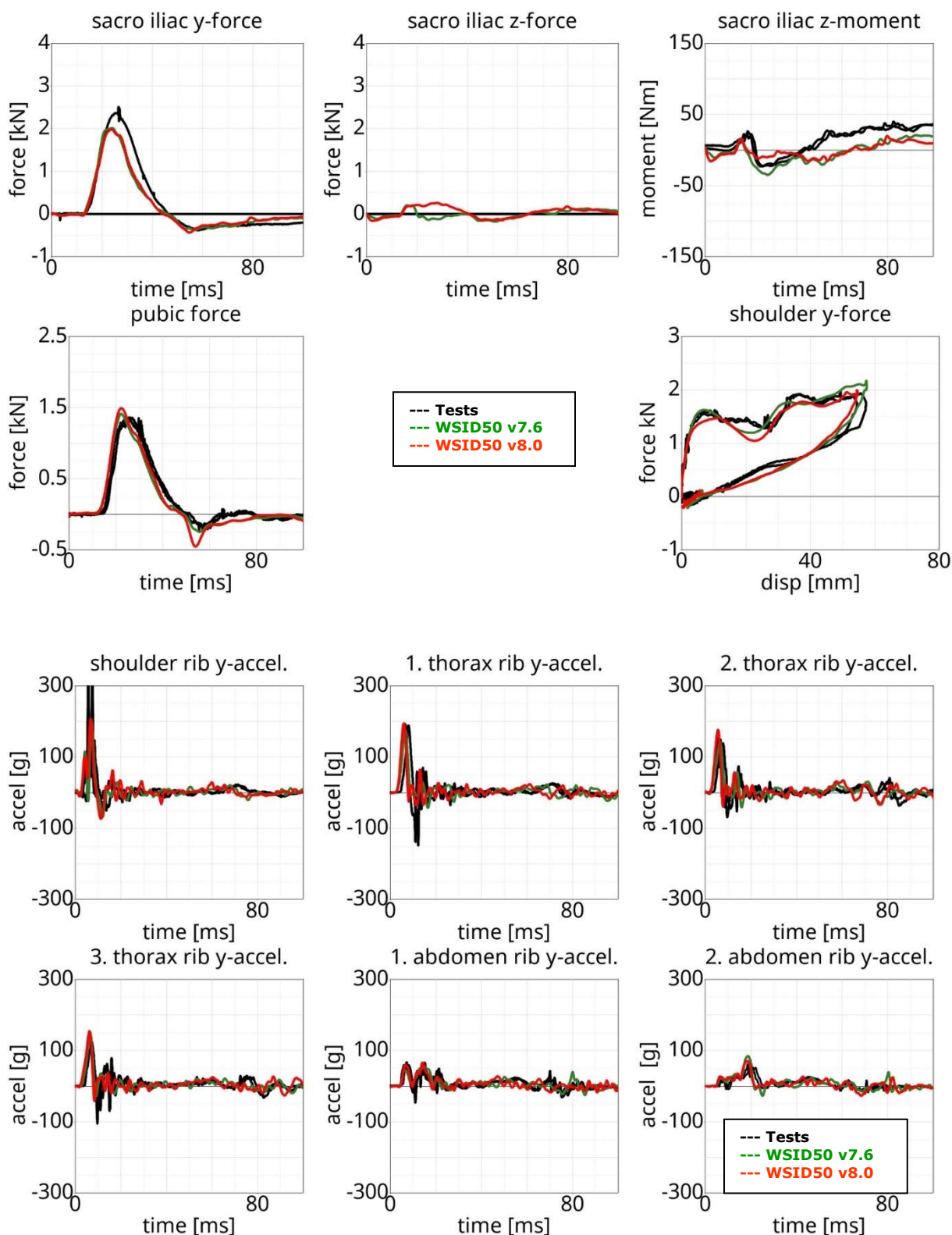


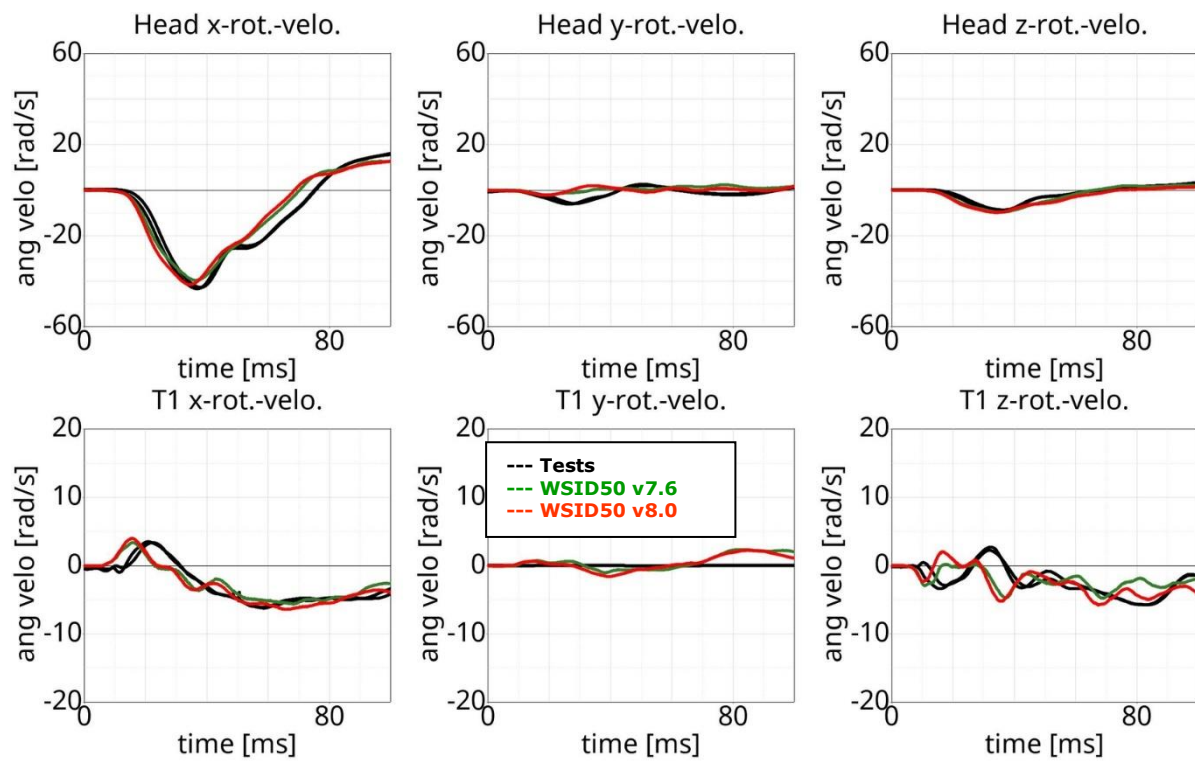
High velocity:





Performance – sled tests





8.3.2 Pelvis shape barrier

8.3.2.1 Arm position second notch

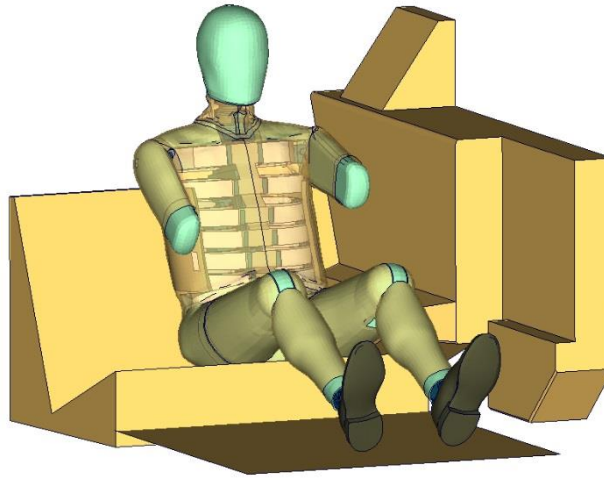
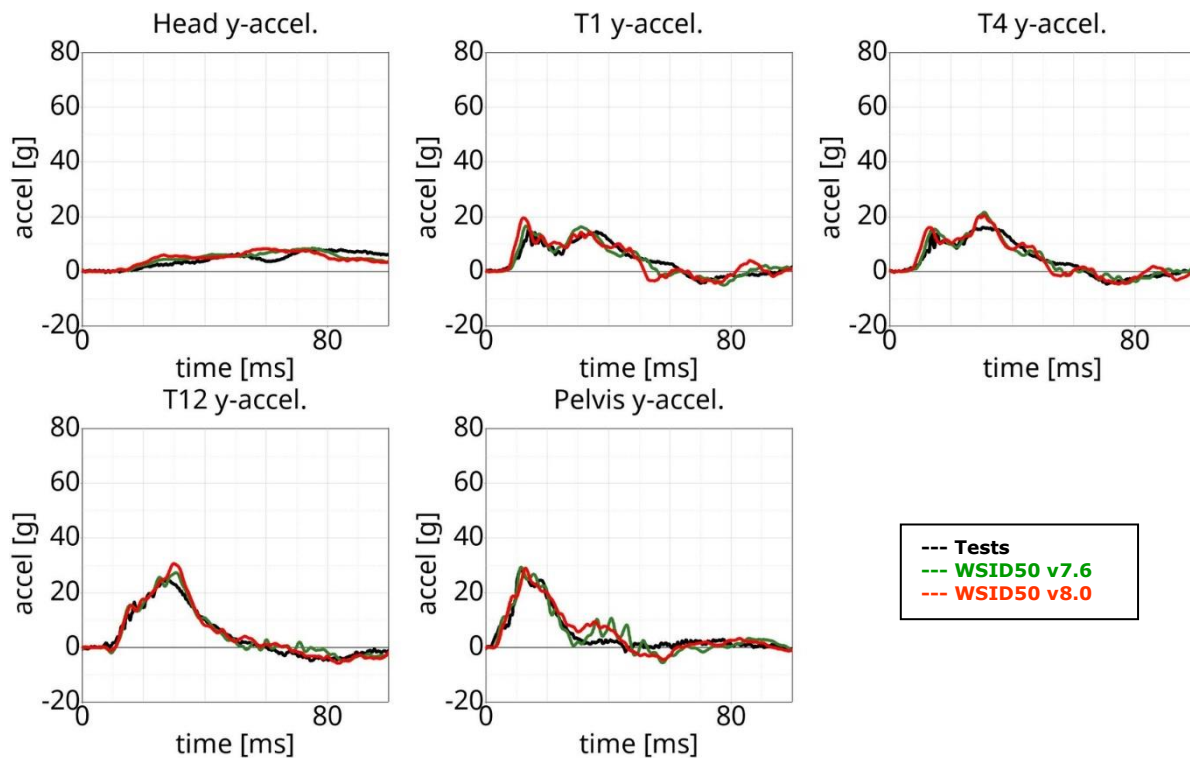
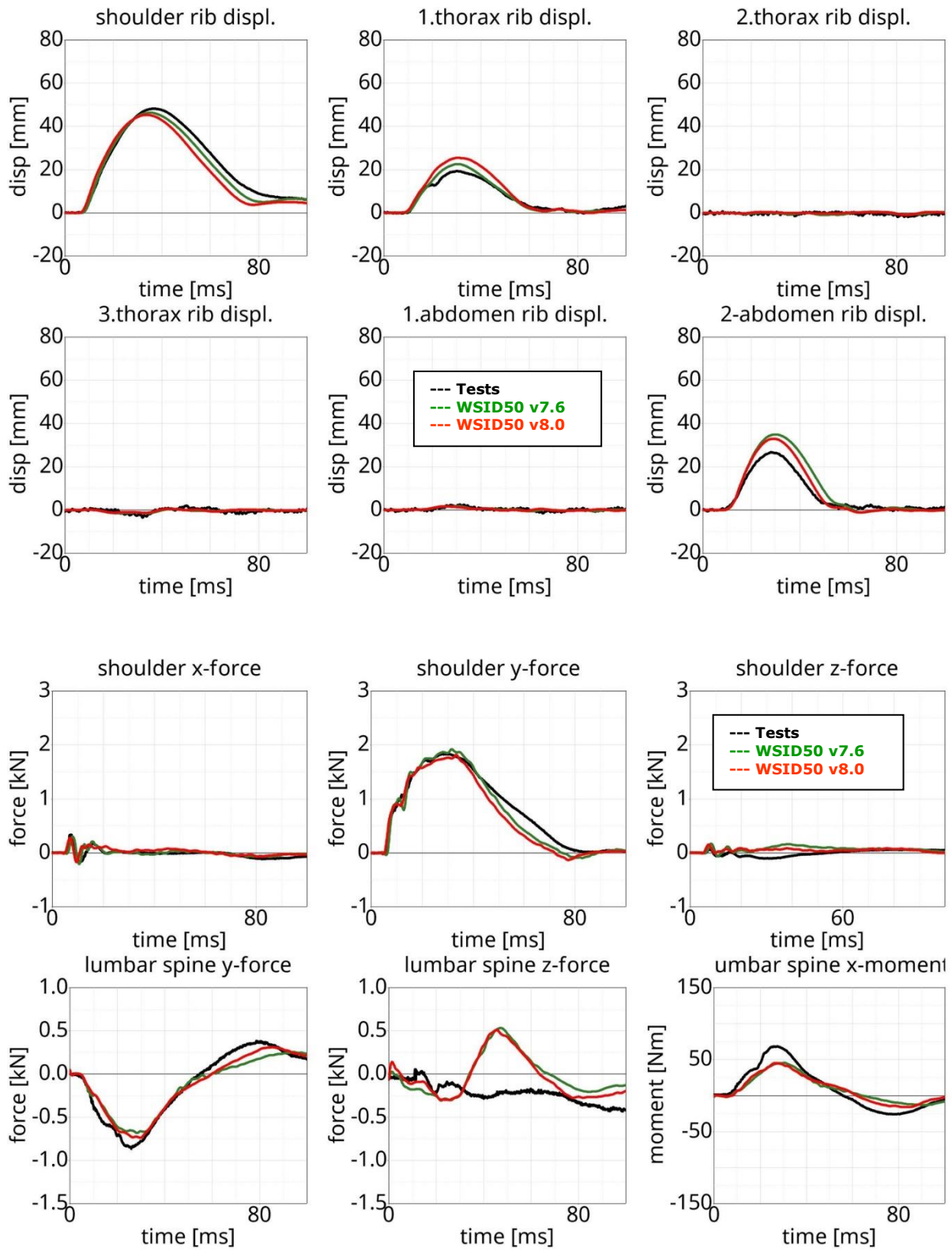


Figure 225: Pelvis barrier and arm second notch.

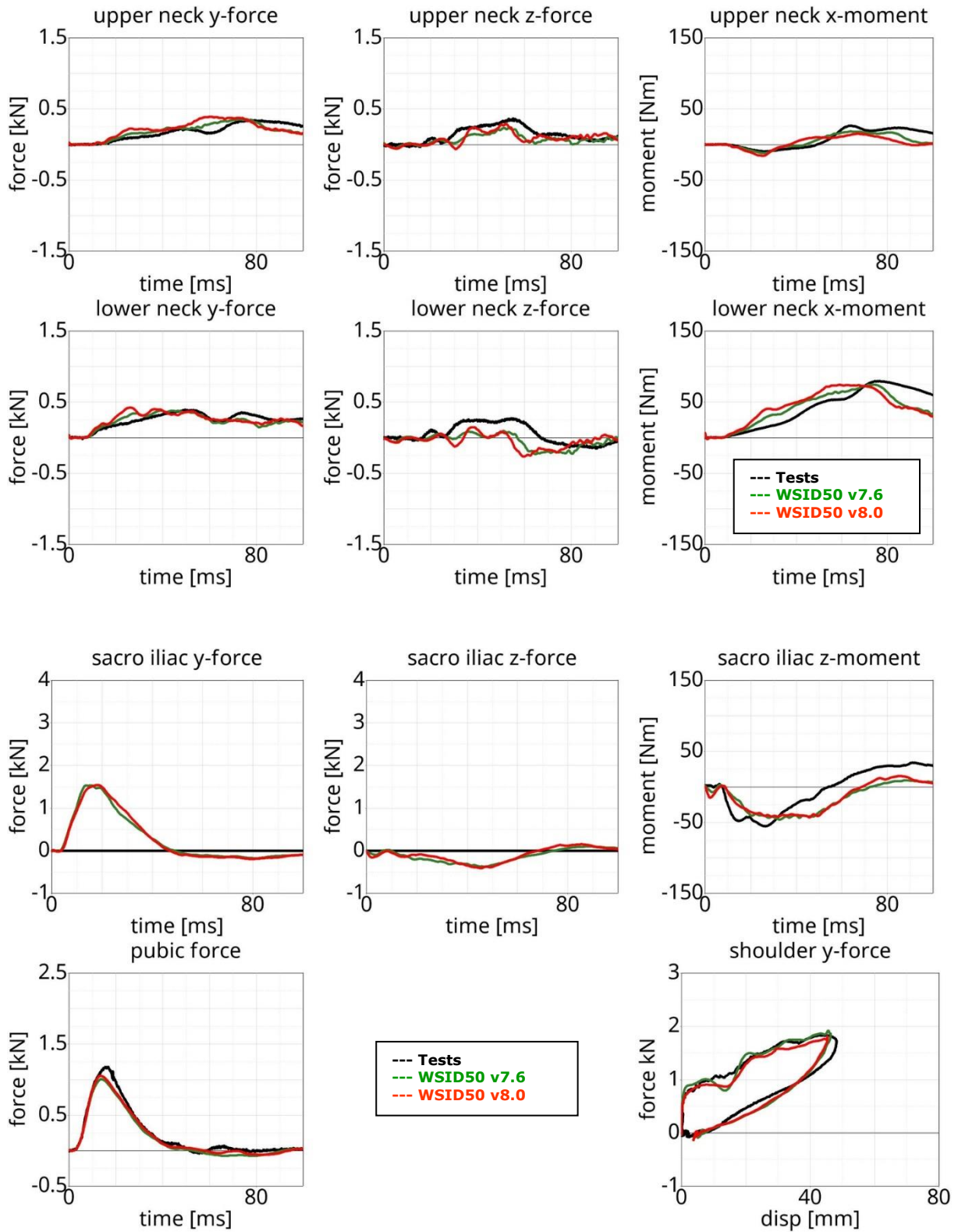
Low velocity:



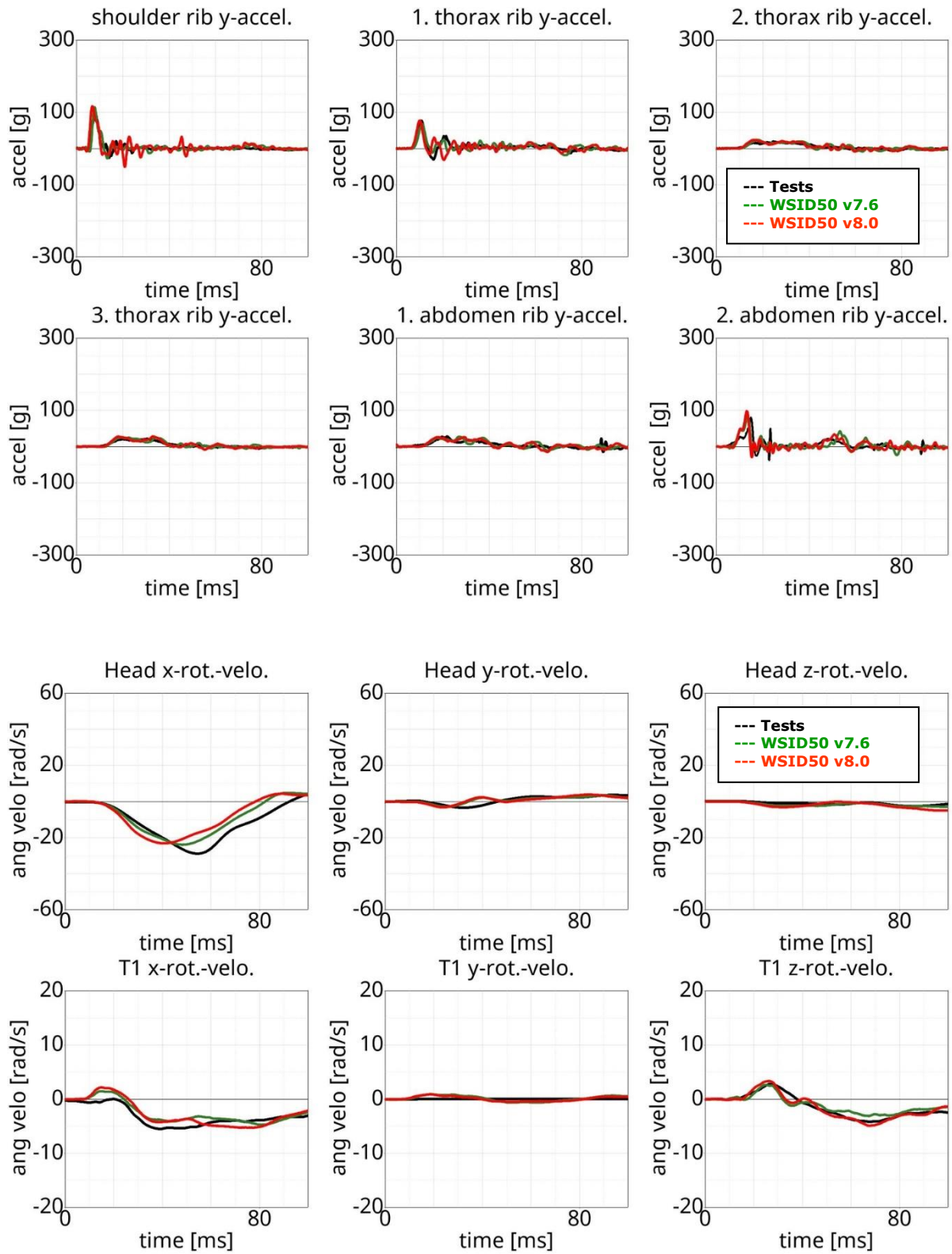
Performance – sled tests



Performance – sled tests



Performance – sled tests



8.3.2.2 Arm position first notch

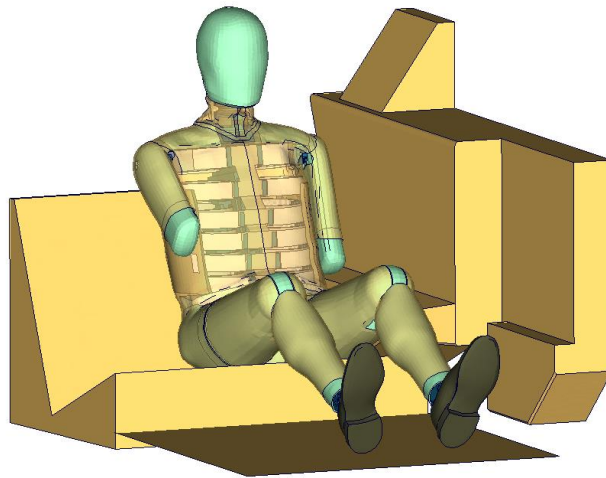
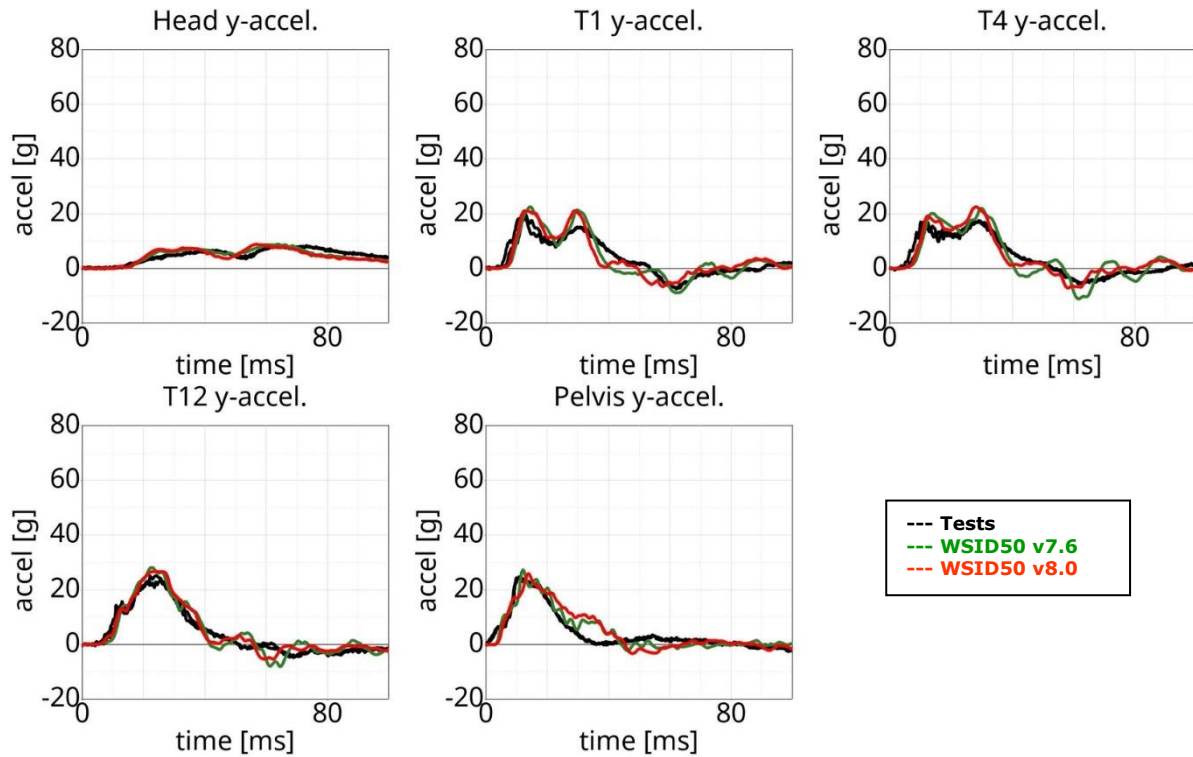
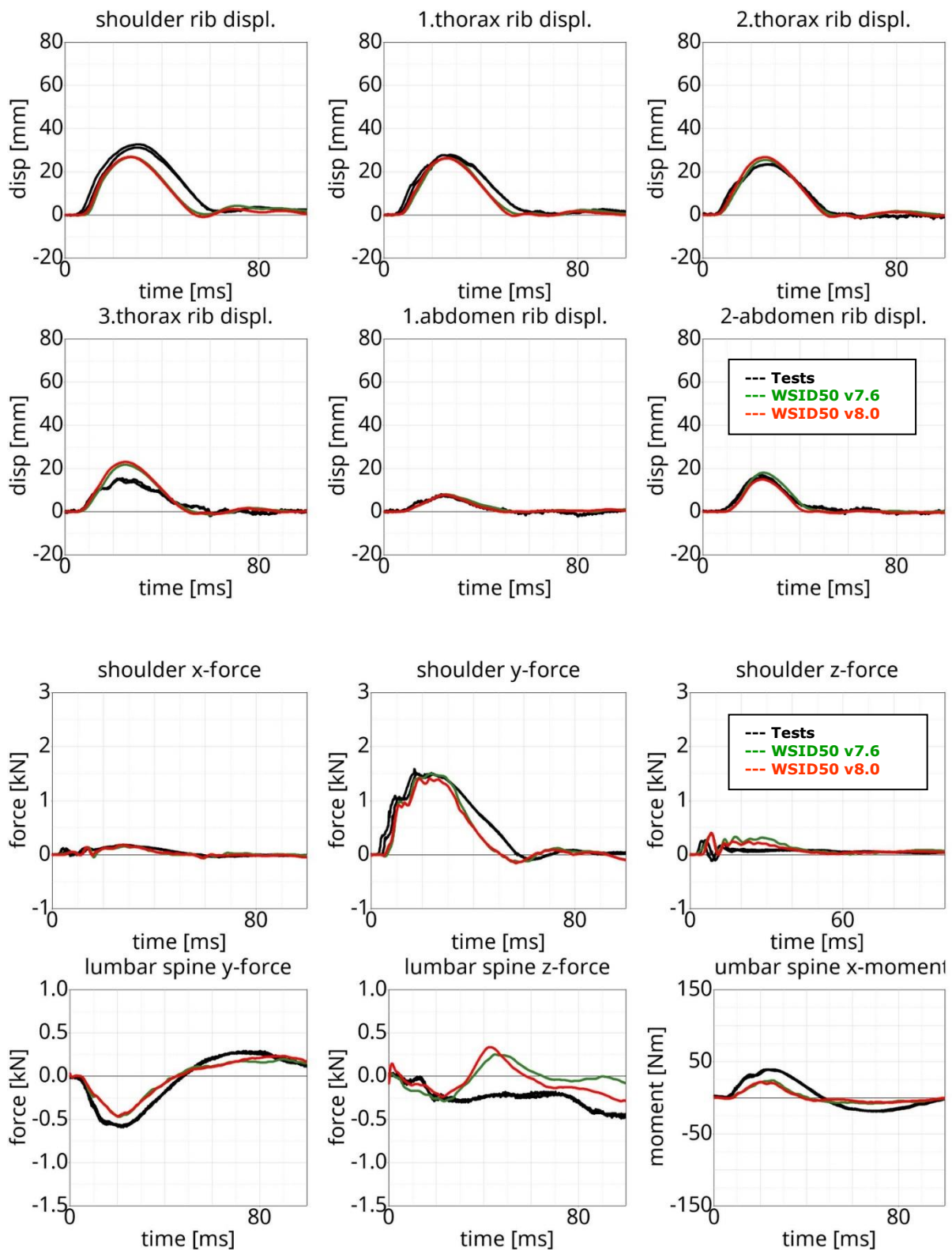


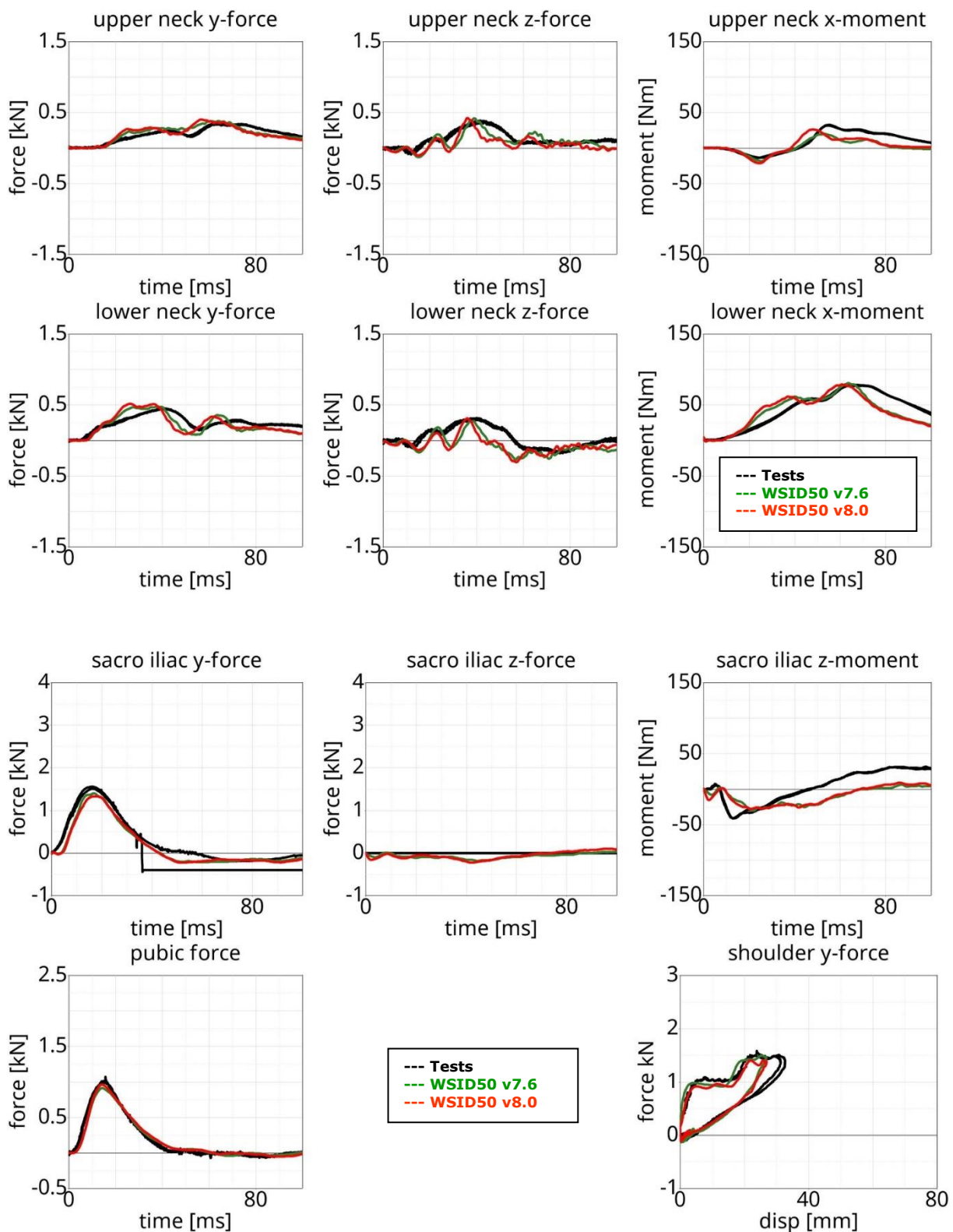
Figure 226: Pelvis barrier and arm first notch.

Low velocity:

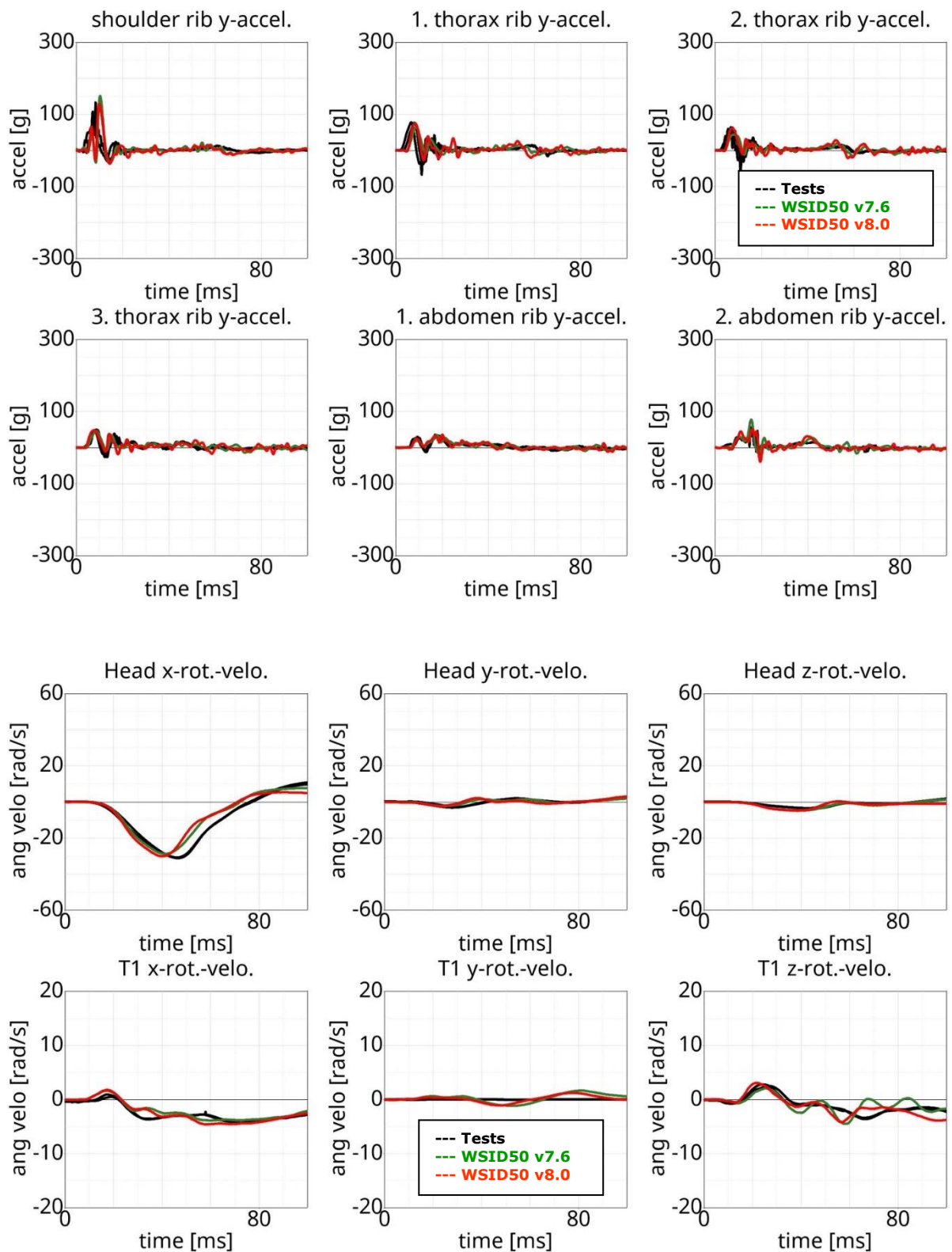




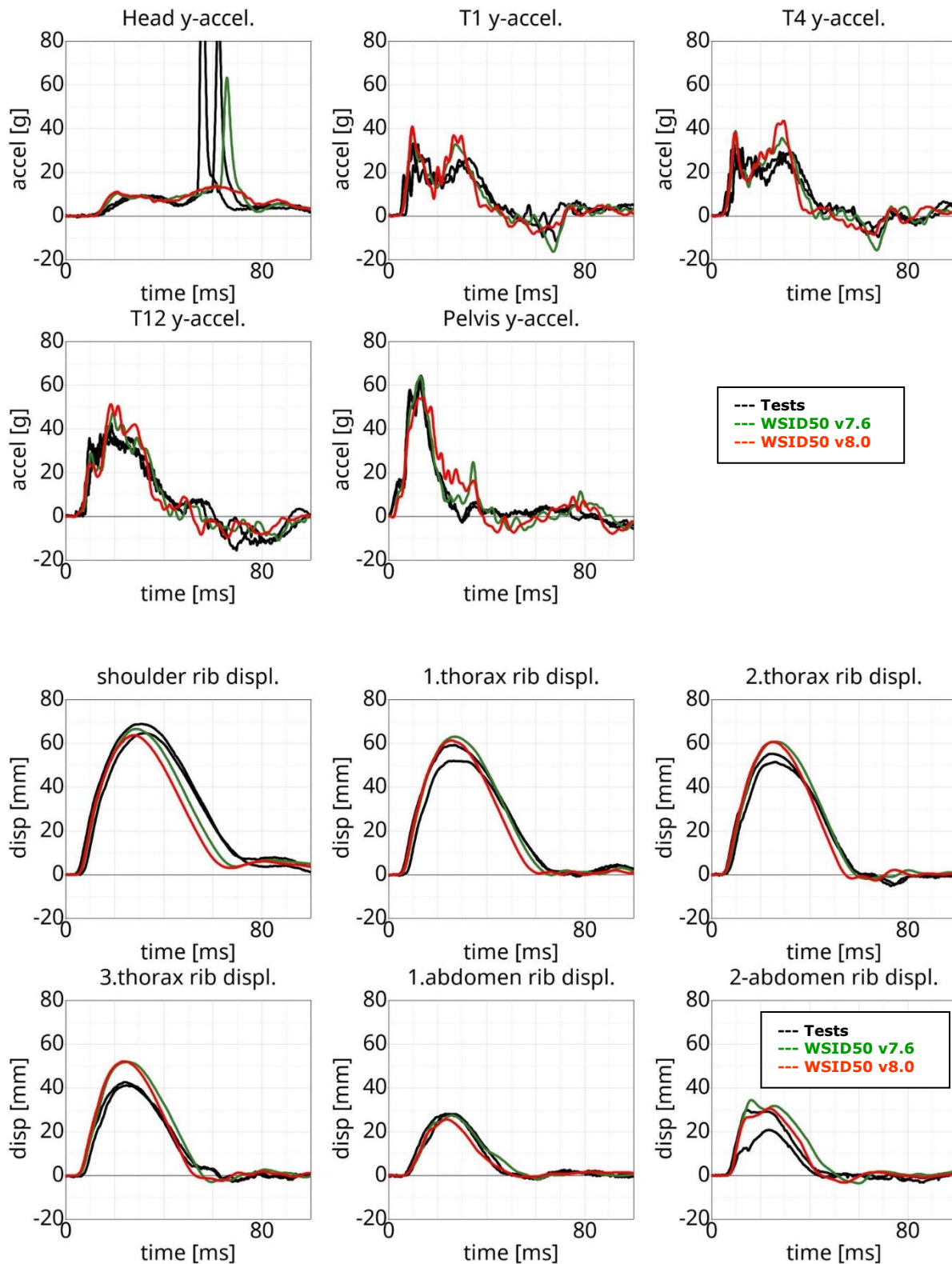
Performance – sled tests

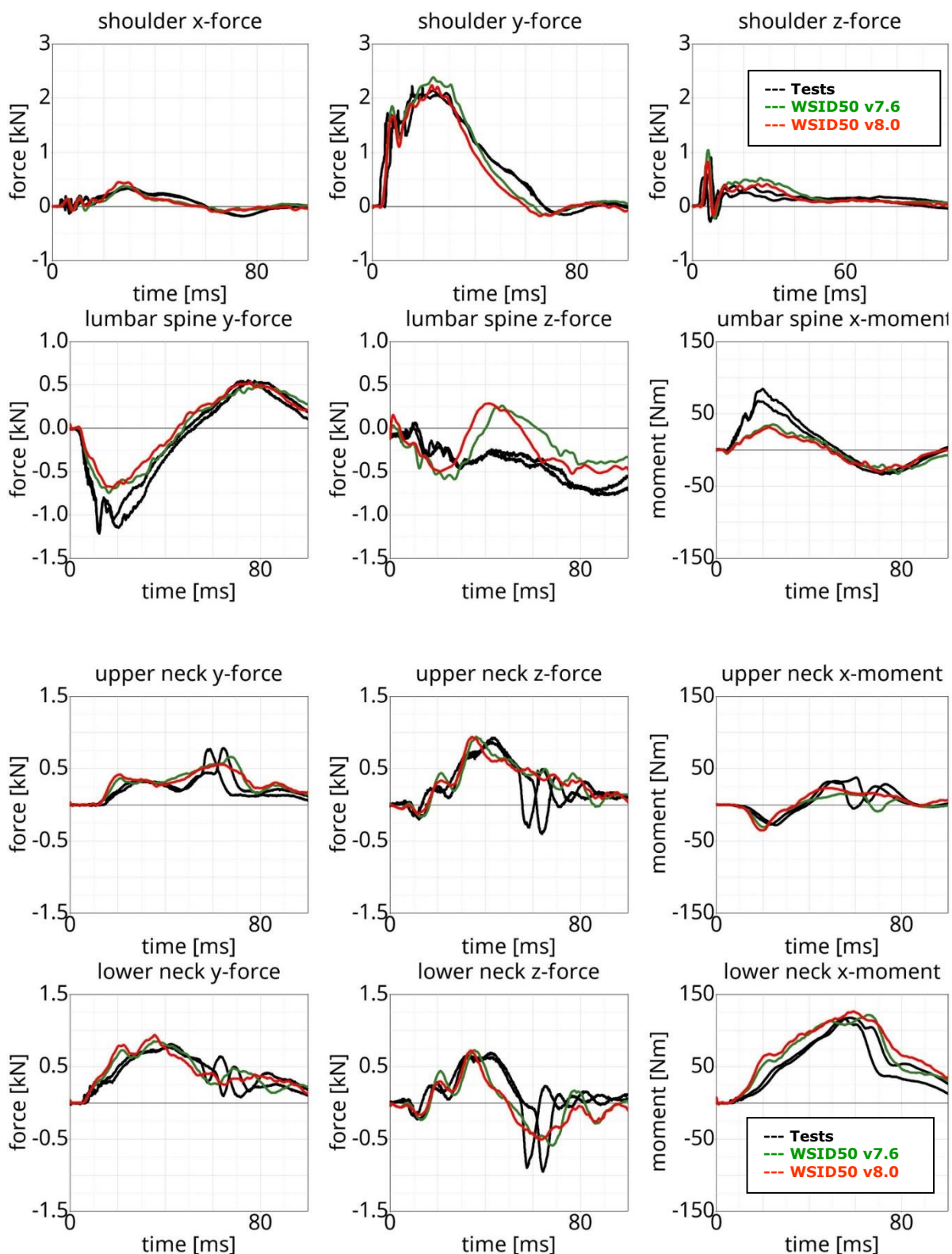


Performance – sled tests

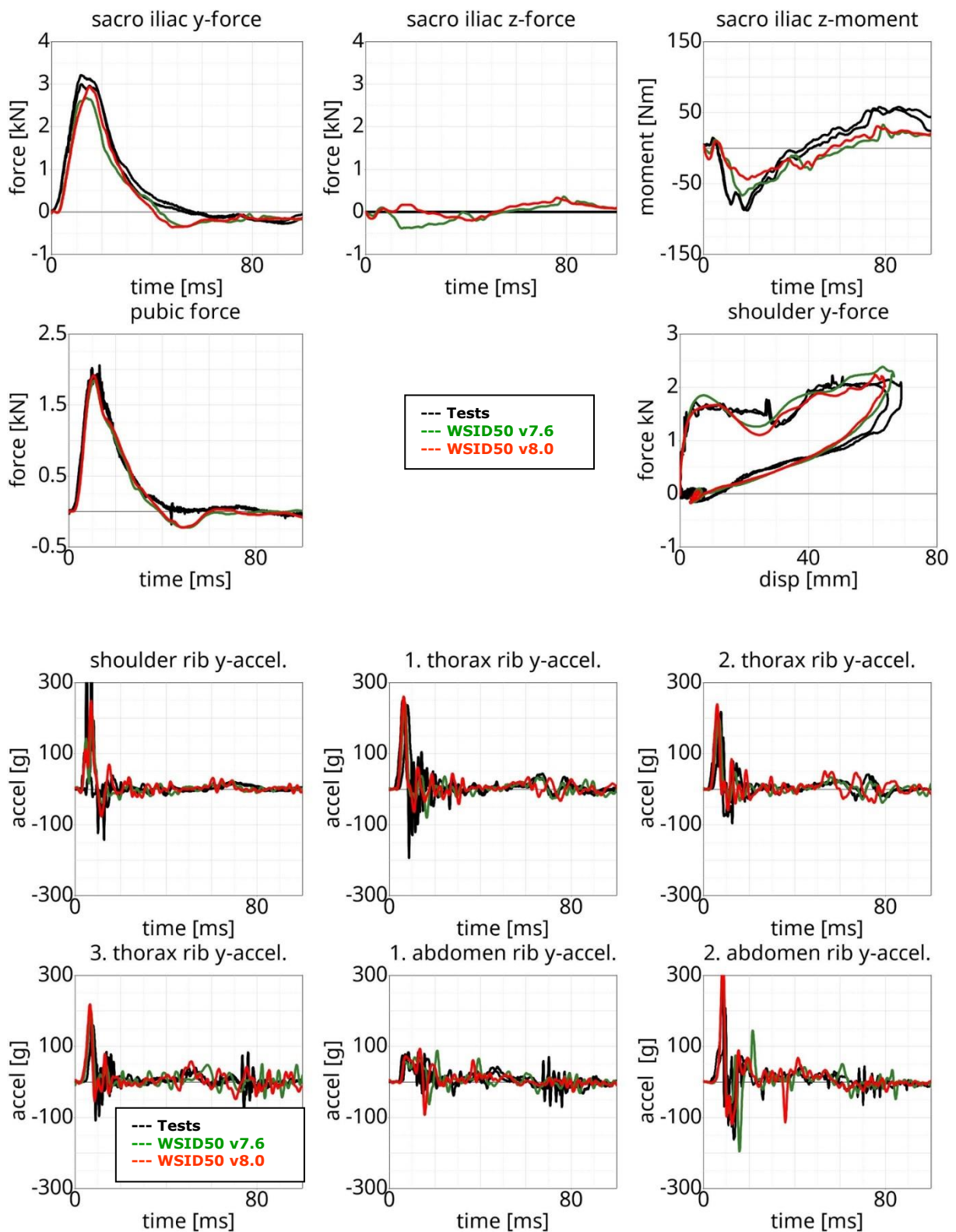


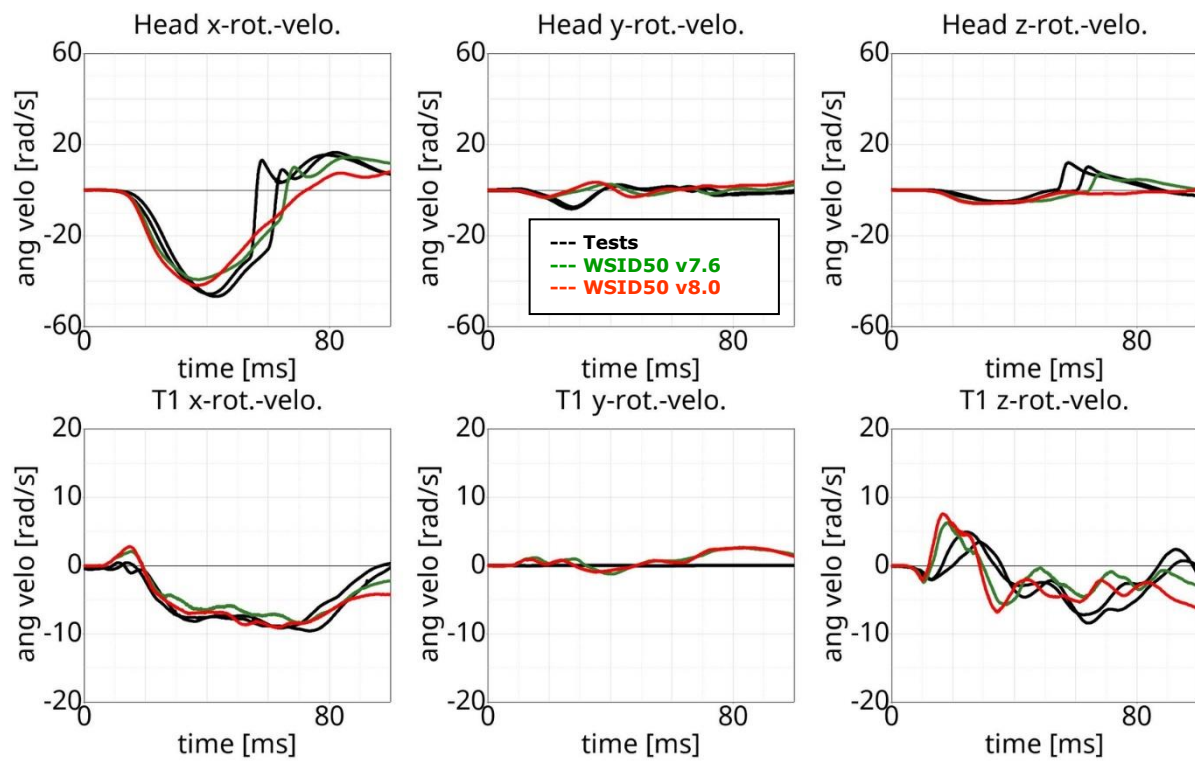
High velocity:





Performance – sled tests





8.3.3 Flat barrier and WorldSID without arm

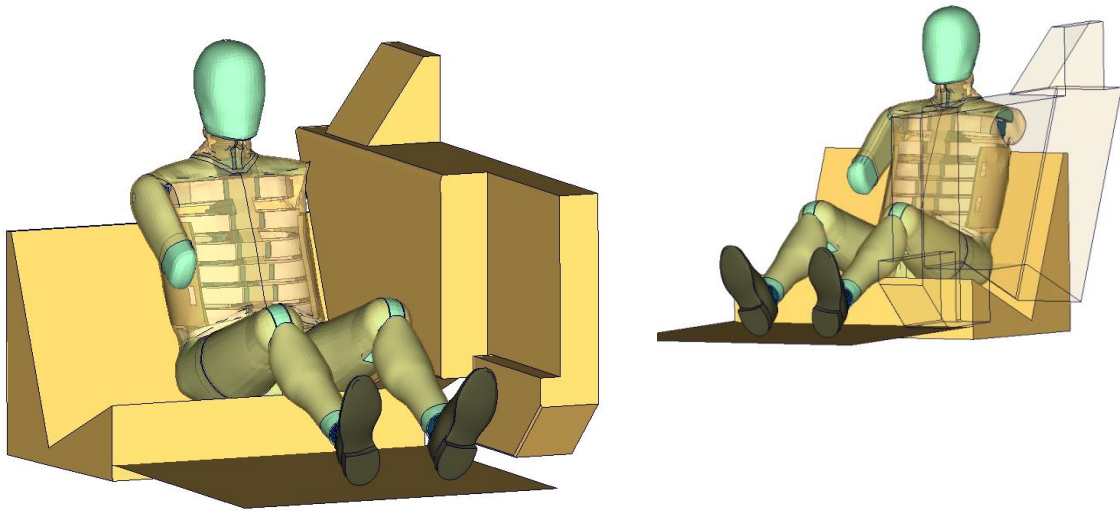
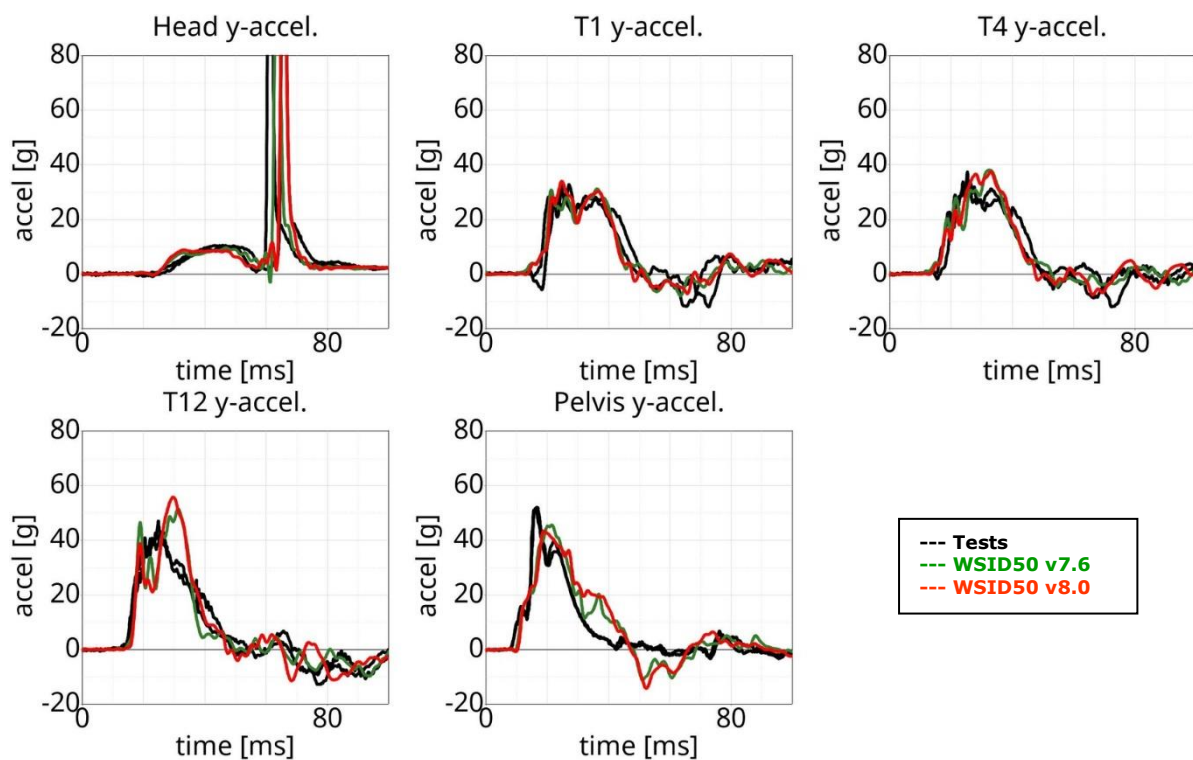
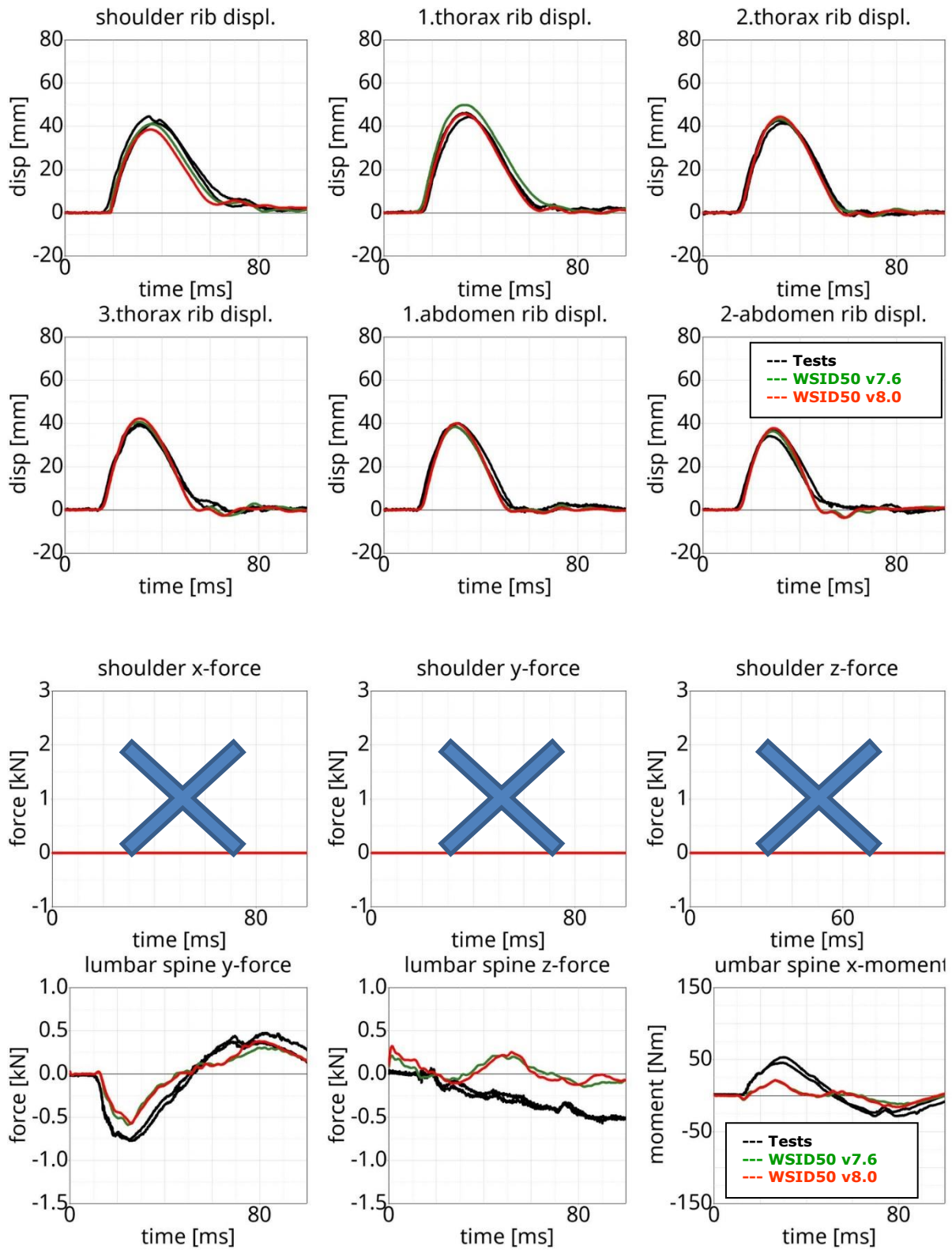


Figure 227: Flat barrier and without arm.

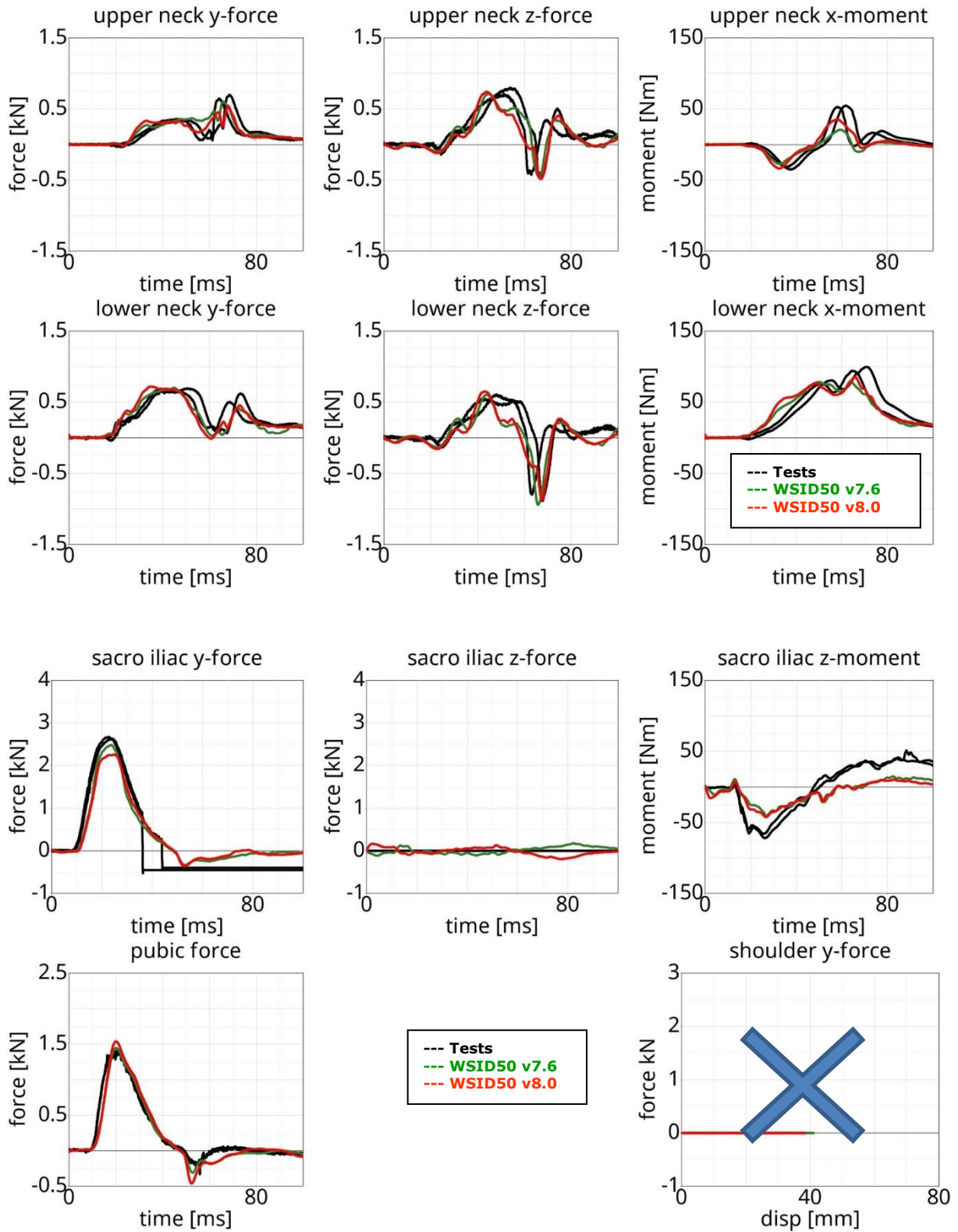
High velocity:



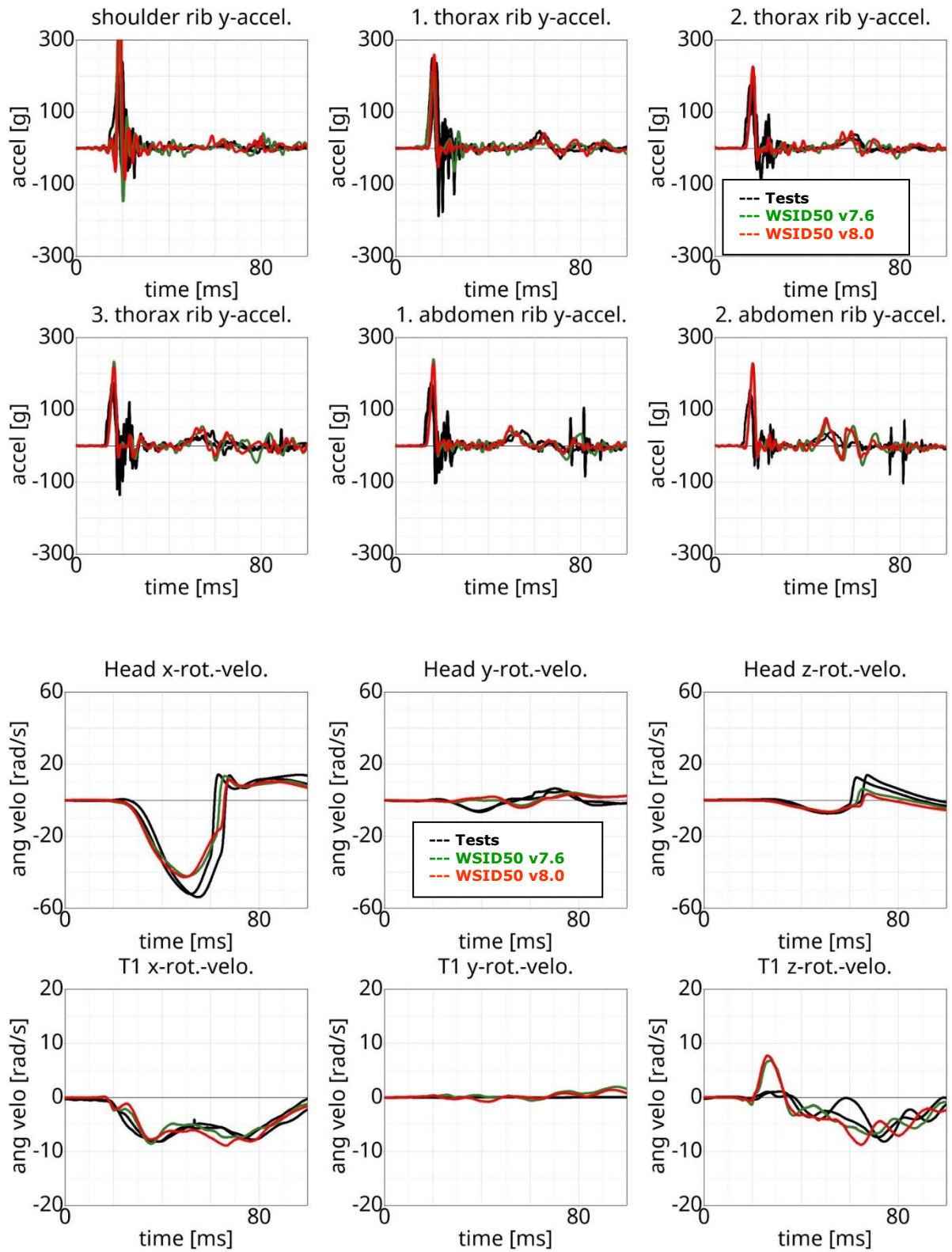
Performance – sled tests



Performance – sled tests



Performance – sled tests



8.3.4 Pelvis shape barrier and WorldSID without Jacket

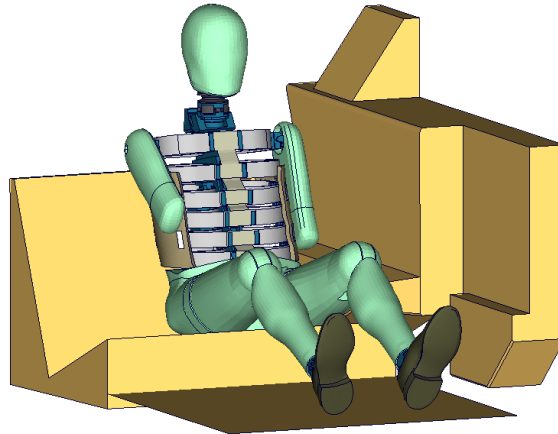
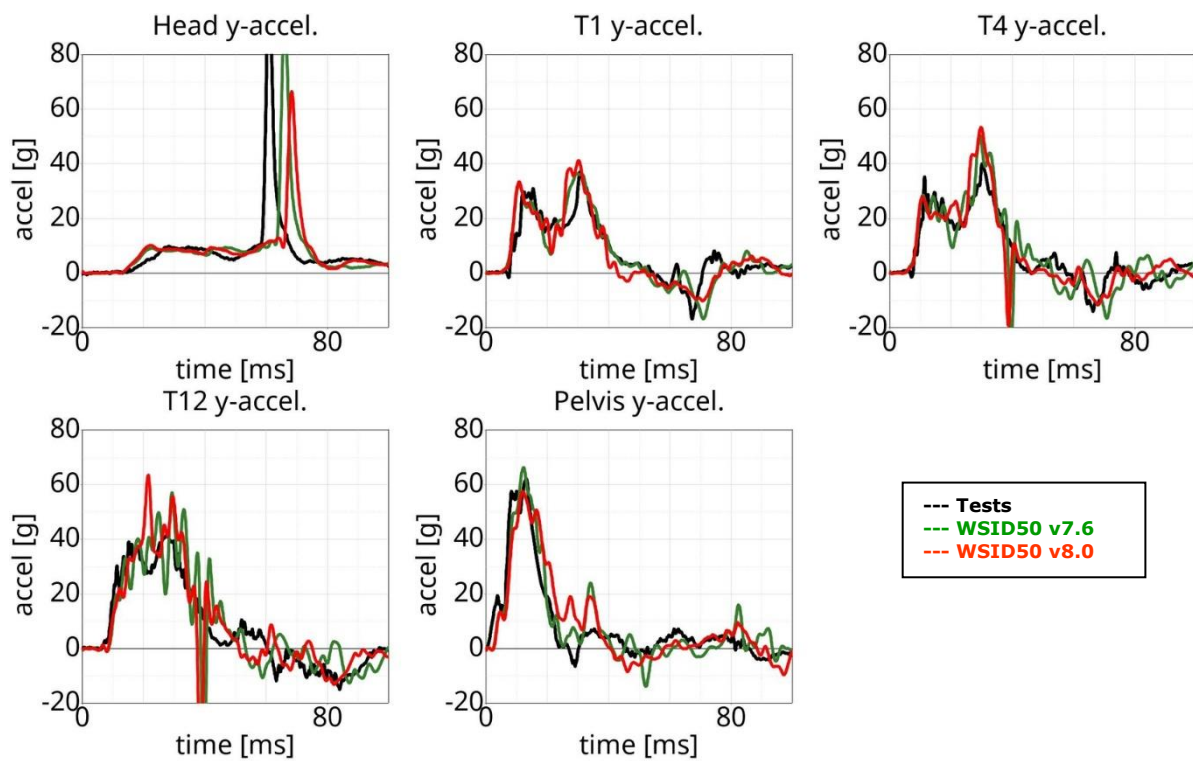
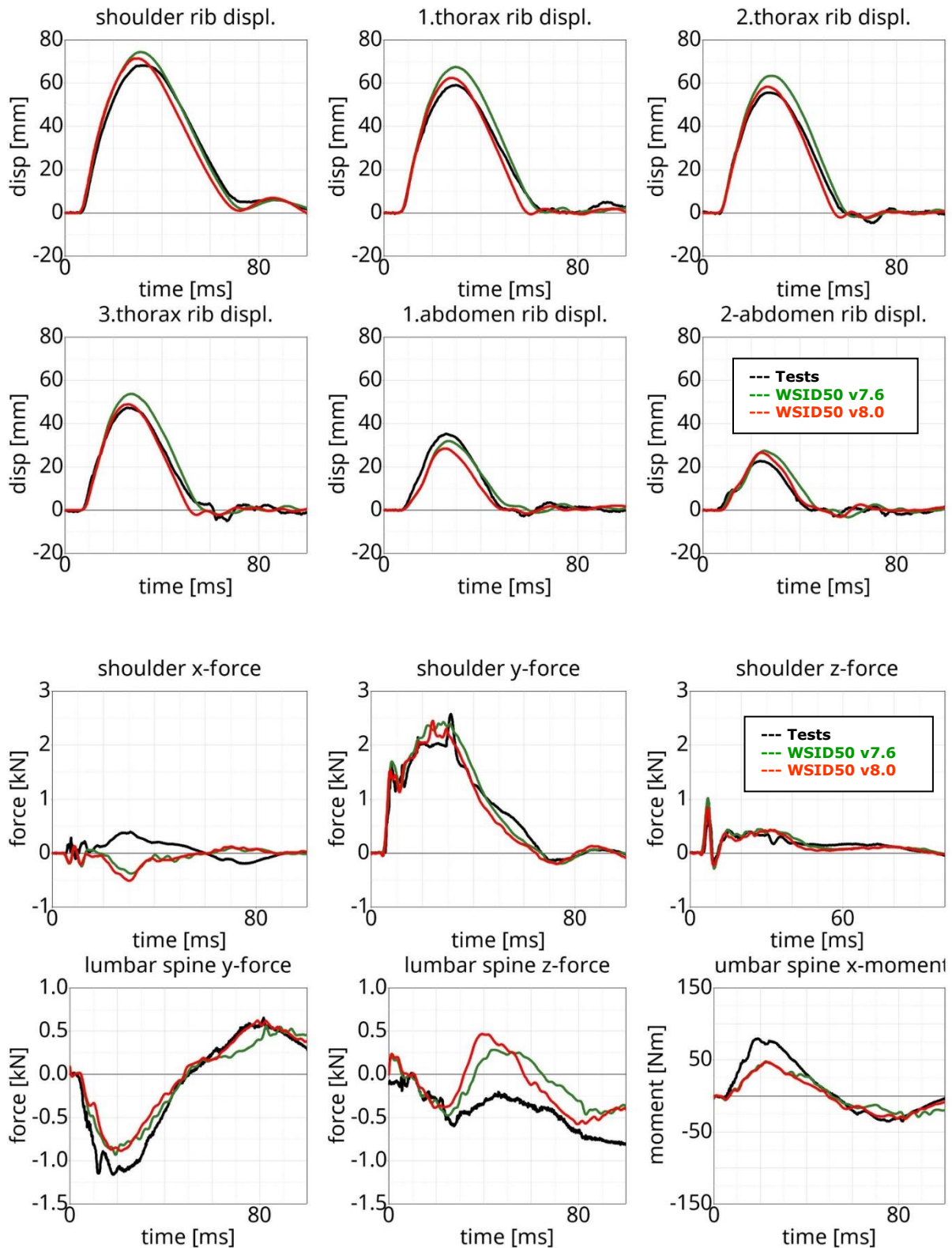


Figure 228: Pelvis barrier and arm first notch without jacket.

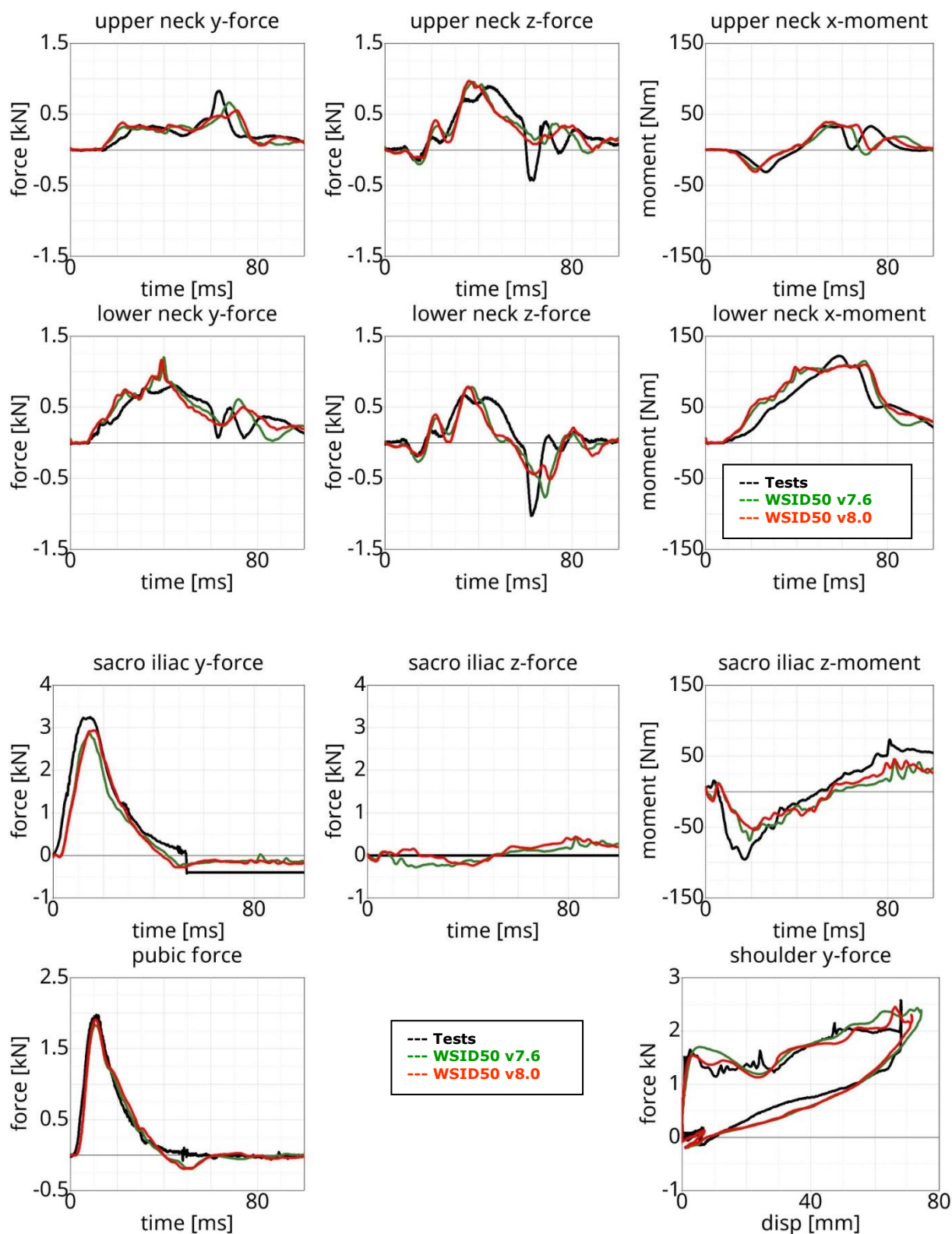
High velocity:

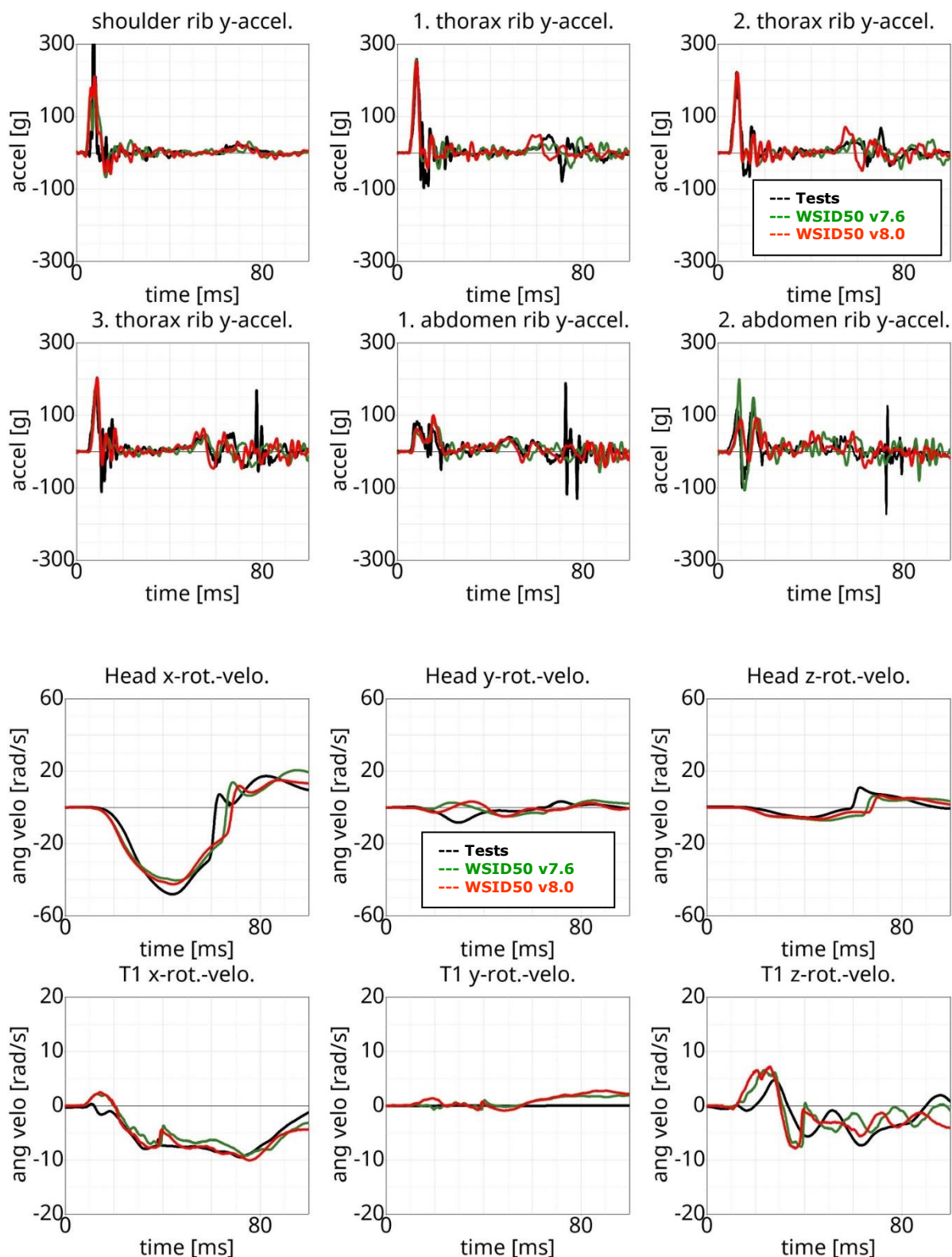


Performance – sled tests



Performance – sled tests





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