BGCE Project: CAD – Integrated Topology Optimization

BGCE First Milestone Meeting

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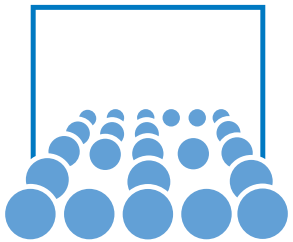
August 5, 2015



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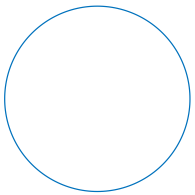
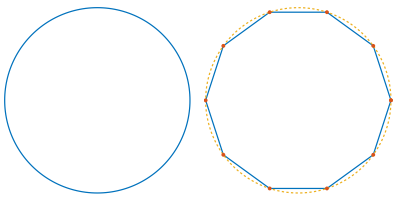
Workflow

CAD design



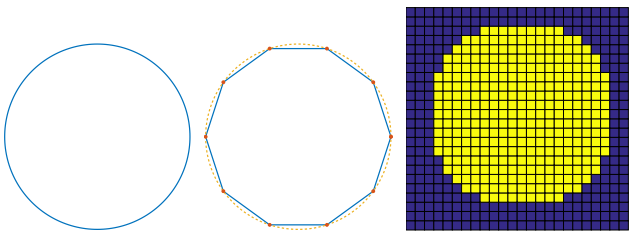
Workflow

STL Interface



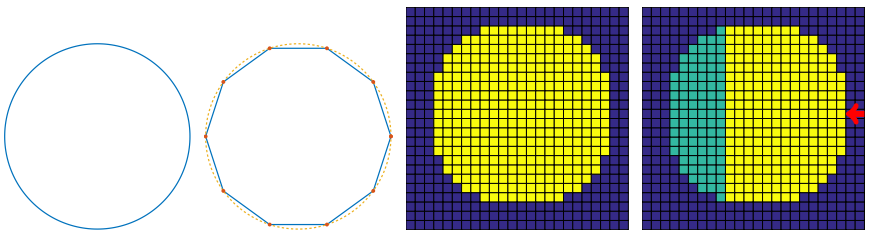
Workflow

Voxelization



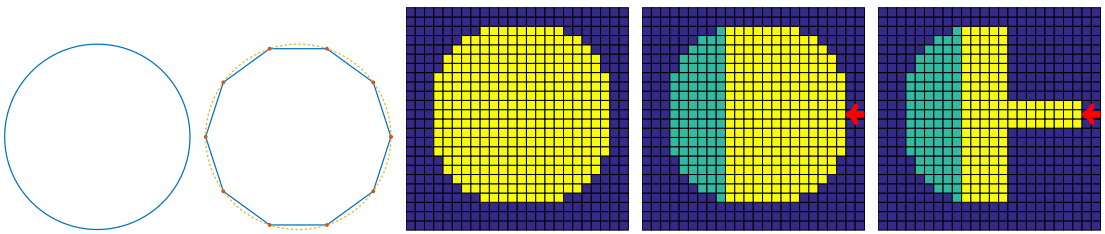
Workflow

TPD input file - Specification of loads and fixtures



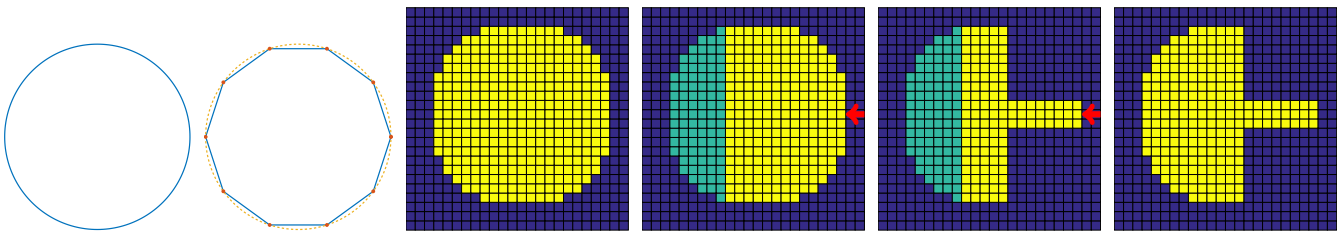
Workflow

Topology optimization



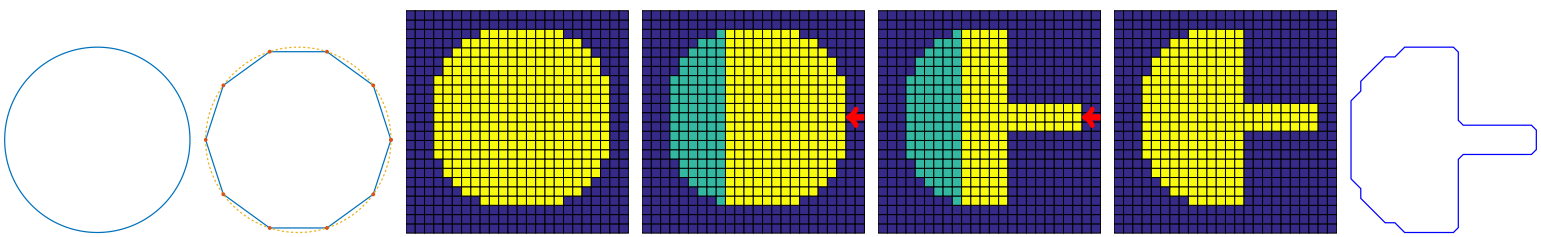
Workflow

Optimized output geometry



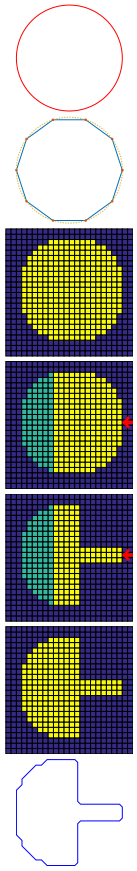
Workflow

Post-processing: Parametrization, Feature recognition



CAD file

Inhalt...



STL file

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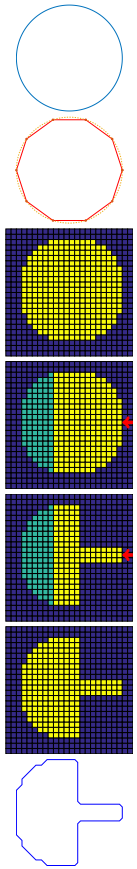

Voxelisation

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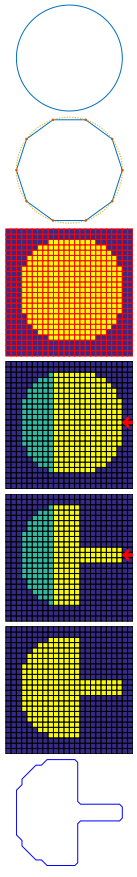

Load and fixture specification

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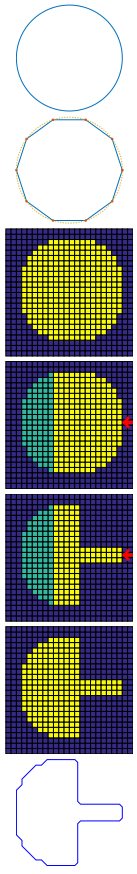
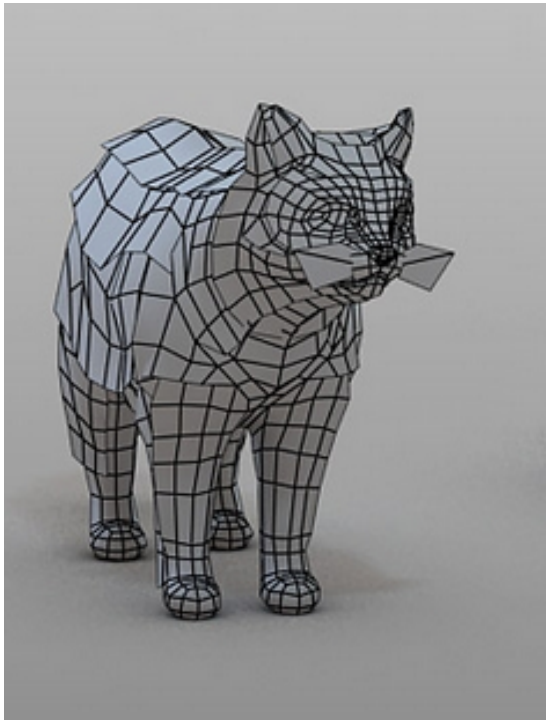


Current status

- What do we have so far?



Current status

- What do we have so far?

- What if we try to pass it to an engineer?

How to make CAD understand our data?

B–Spline

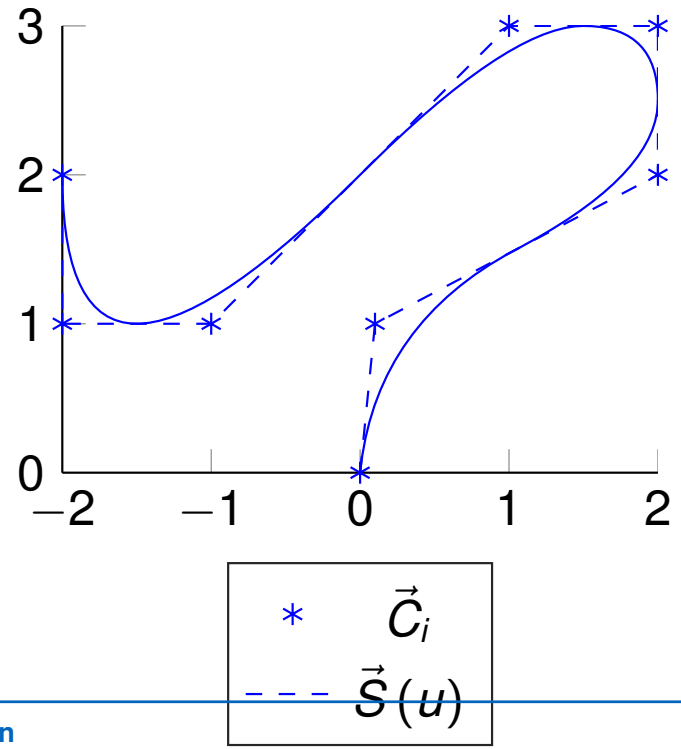
$$\vec{S}(u,v) = \sum_{i,j=1}^{n,m} \vec{C}_{i,j} N_i^p(u) N_j^p(v),$$

where p – degree of the B–Spline surface and n, m – number of control points in each direction.

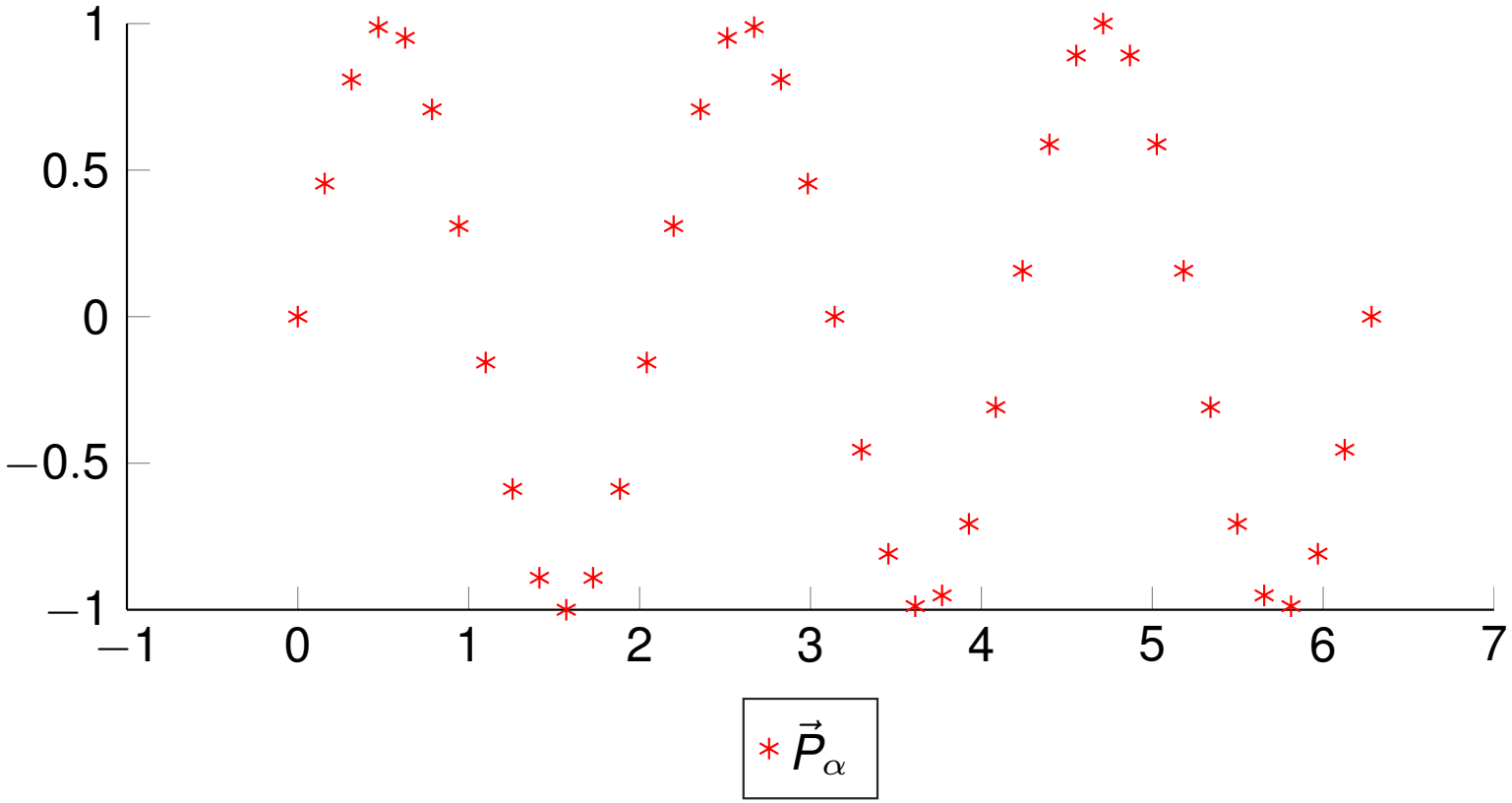
B–Splines

- offer great flexibility for handling arbitrary shapes
- are CAD–standard

Engineers are working with CAD



B–Spline Fitting

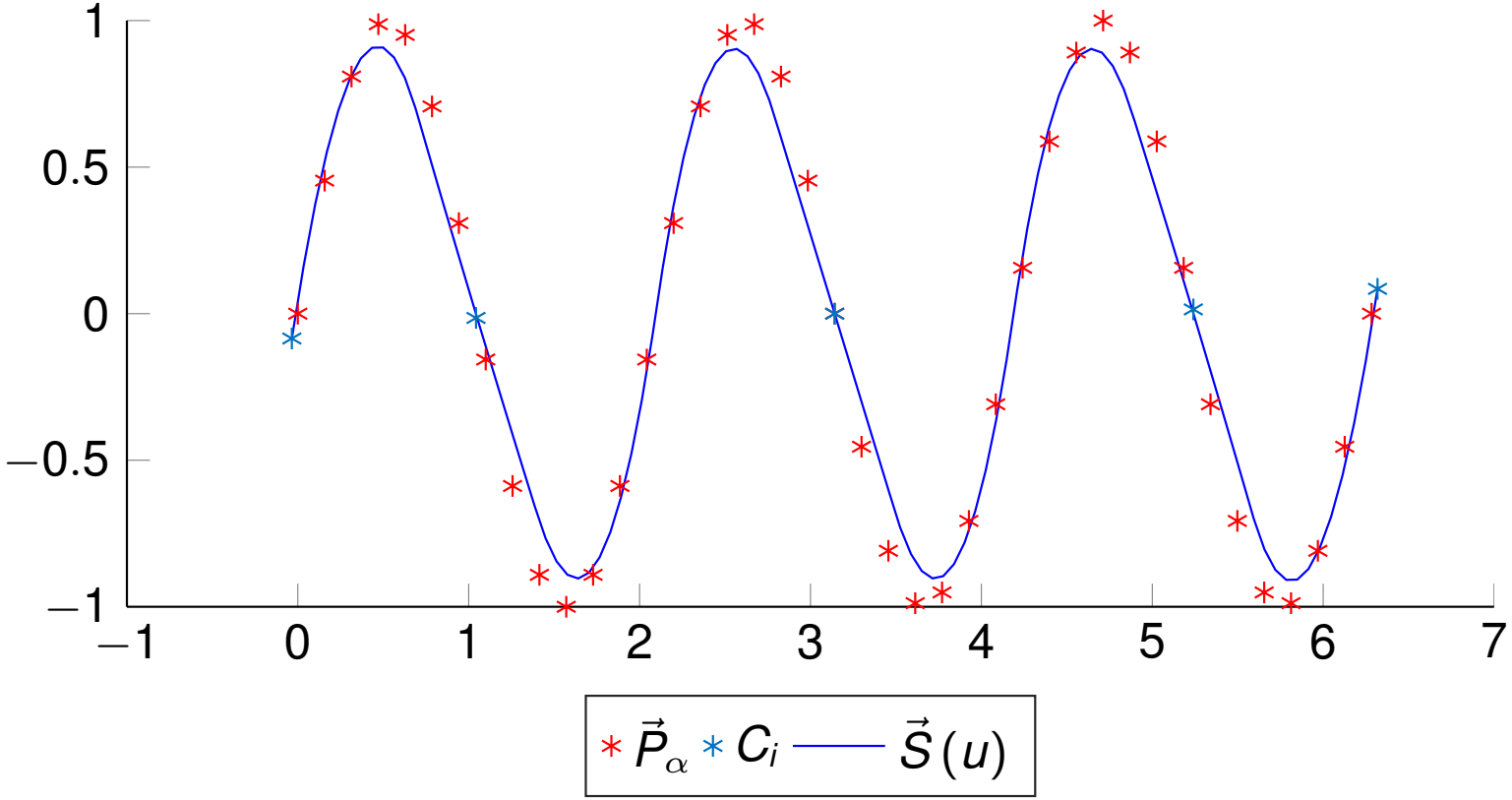


Goal:

Find B–Spline representation of our data!

$$\vec{S}(u_\alpha, v_\alpha) \approx \vec{P}_\alpha$$

B–Spline Fitting



Goal:

Find B–Spline representation of our data!

$$\vec{S}(u_\alpha, v_\alpha) \approx \vec{P}_\alpha$$

B–spline fitting: Least squares

The task:

Find control points $C_{i,j}$, such that the B–Spline surface

$$\vec{S}(u,v) = \sum_{i,j=1}^{n,m} \vec{C}_{i,j} N_i^p(u) N_j^p(v)$$

approximates our dataset of points $\left\{\vec{P}_\alpha\right\}$.

This leads to *minimization problem*:

$$\vec{S}(u_\alpha, v_\alpha) \approx \vec{P}_\alpha \forall \alpha \leftrightarrow \min_{\vec{C}_{i,j} \in \mathbb{R}^3} \sum_\alpha \| \vec{P}_\alpha - \vec{S}(u_\alpha, v_\alpha) \|_2$$

B–spline fitting: Least squares (cont.)

Resulting system looks like:

$$\sum_{i,j=1}^{n,m} \vec{C}_{i,j} N_i^p(u_\alpha) N_j^p(v_\alpha) \approx \vec{P}_\alpha \quad \forall \alpha$$

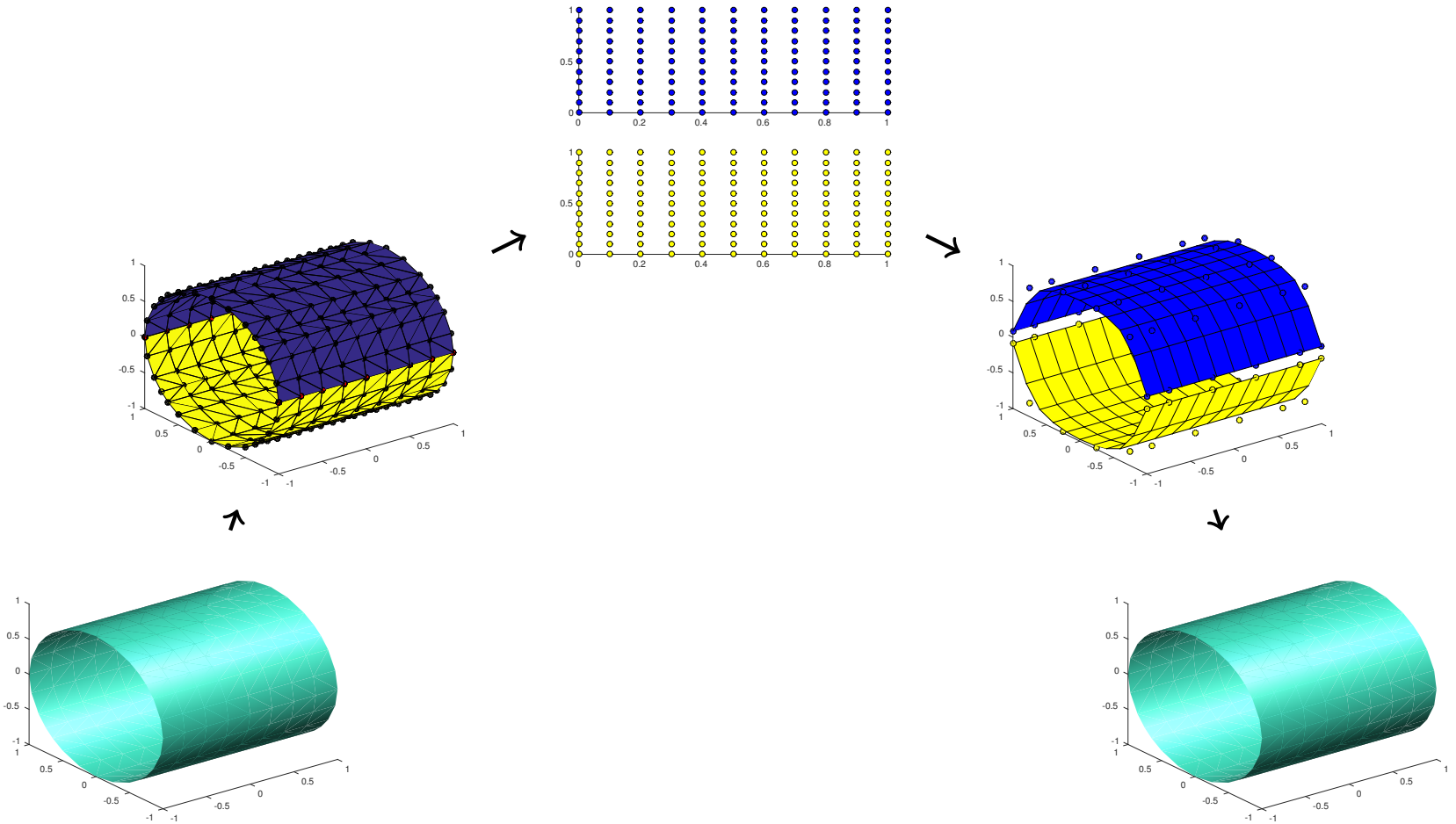
Or, in matrix–vector form:

$$AC \approx P$$

Our system matrix A depends on $\{u_\alpha, v_\alpha\}$

B–Spline Fitting pipeline according to Becker, Schäfer, Jameson

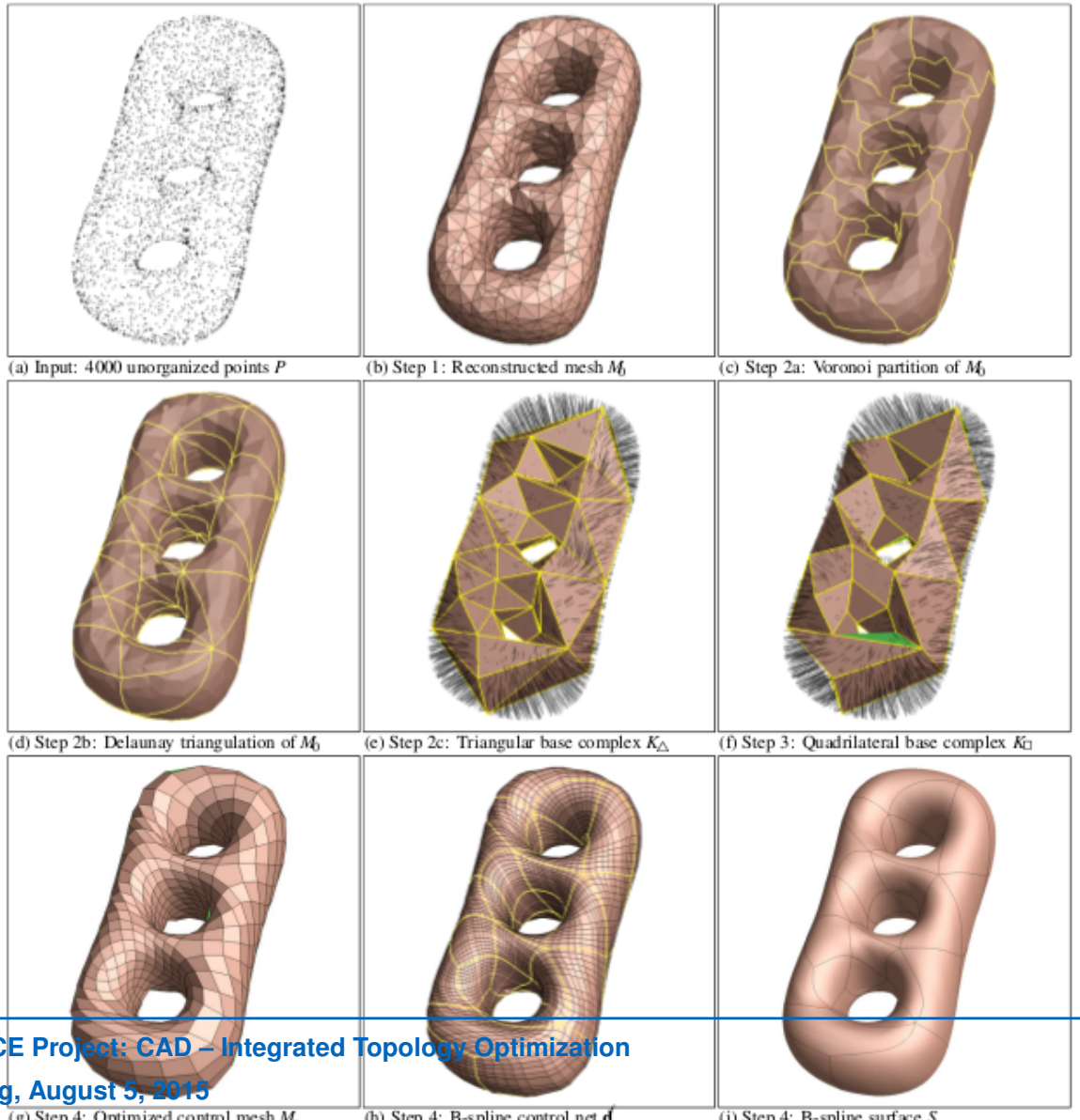
How to deal with a complex shape?



B–Spline Fitting: Open questions

- How to distribute our data into patches?
- How to parametrize obtained patches?
- How to connect several patches after fitting?

B–Spline Fitting pipeline according to M. Eck& H. Hoppe

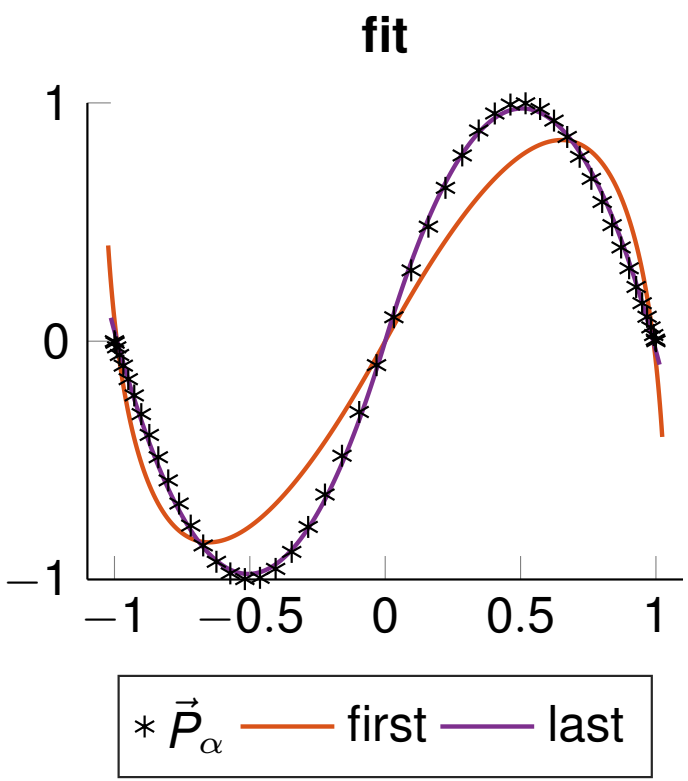


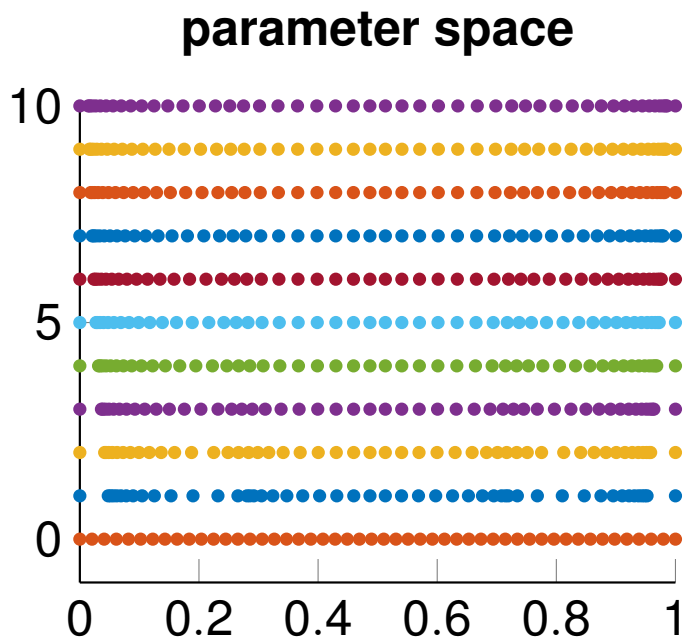
(a) Input: 4000 unorganized points P
(b) Step 1: Reconstructed mesh M_0
(c) Step 2a: Voronoi partition of M_0
(d) Step 2b: Delaunay triangulation of M_0
(e) Step 2c: Triangular base complex $K_\triangle$
(f) Step 3: Quadrilateral base complex $K_\square$
(g) Step 4: Optimized control mesh M
(h) Step 4: B-spline control net $\mathbf{d}$
(i) Step 4: B-spline surface S

B–Spline Fitting: Parameter correction

The task:

For *fixed* control points $C_{i,j}$, find an optimal parametrization $\{u_\alpha, v_\alpha\}$.





Summary

What's done?

- first part of the pipeline from CAD model to optimized voxel model
- identified crucial points in the fitting problem

Outlook

What's next?

- further work on M.Eck & H.Hoppe paper
- search for algorithm which considers voxel geometry