

JSC Engineering Orbital Dynamics Contact Model

Simulation and Graphics Branch (ER7)
Software, Robotics, and Simulation Division
Engineering Directorate

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National Aeronautics and Space Administration
Lyndon B. Johnson Space Center
Houston, Texas

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Abstract

The Contact Model is designed to provide a way for dynamic bodies created with the Dynamic Body Model [2] to interact beyond mere mass attachment. Without the Contact Model, dynamic bodies are completely separate entities that can not influence each other's state if they are not attached via a mass tree [6]. Using the Contact Model surfaces can be defined which generate forces when they are inter-penetrated (contacted) by surfaces on other dynamic bodies. The basic infrastructure provided by the Contact Model is designed to be extended allowing for the simulation of detailed docking, grappling, and birthing operations.

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Chapter 1

Introduction

1.1 Purpose and Objectives of the Contact Model

The Contact Model is designed to provide a way for dynamic bodies created with the Dynamic Body Model [2] to interact beyond mere mass attachment. Without the Contact Model, dynamic bodies are completely separate entities that can not influence each other's state if they are not attached via a mass tree [6]. Using the Contact Model surfaces can be defined which generate forces when they are inter-penetrated (contacted) by surfaces on other dynamic bodies. The basic infrastructure provided by the Contact Model is designed to be extended allowing for the simulation of detailed docking, grappling, and birthing operations.

1.2 Context within JEOD

The following document is parent to this document:

- *JSC Engineering Orbital Dynamics* [3]

The Contact Model forms a component of the interactions suite of models within JEOD v5.2. It is located at models/interactions/contact.

1.3 Document History

Author	Date	Revision	Description
Christopher Thebeau	04JAN2012	1.2	model redesign
Christopher Thebeau	24SEP2010	1.1	initial version
Christopher Thebeau	23JUL2010	1.0	draft version

1.4 Document Organization

This document is formatted in accordance with the NASA Software Engineering Requirements Standard [4].

The document comprises chapters organized as follows:

Chapter 1: Introduction -This introduction describes the objective and purpose of the Contact Model.

Chapter 2: Product Requirements -The requirements chapter describes the requirements on the Contact Model.

Chapter 3: Product Specification -The specification chapter describes the architecture and design of the Contact Model.

Chapter 4: User Guide -The user guide chapter describes how to use the Contact Model.

Chapter 5: Inspections, Tests, and Metrics -The inspections, tests, and metrics describes the procedures and results that demonstrate the satisfaction of the requirements for the Contact Model.

Chapter 2

Product Requirements

Requirement Contact_1: JEOD Requirements

Requirement:

This model shall meet the JEOD project requirements specified in the JEOD v5.2 [top-level document \[3\]](#) .

Rationale:

This model shall, at a minimum, meet all external and internal requirements applied to the JEOD v5.2 release.

Verification:

Inspection

Requirement Contact_2: Contact Between Surfaces in 3D Space

Requirement:

The Contact Model shall determine if two or more 3D surfaces are in contact and resolve the resultant forces utilizing user defined dynamics.

Rationale:

Contact between surfaces is the core functionality of the Contact Model.

Verification:

Inspection, Test

Requirement Contact_3: Provide a Default Contact Force Model Based on Springs

Requirement:

The Contact Model shall provide default contact dynamics functionality based on simple springs.

Rationale:

A basic contact force generation model needed to be provided with the Contact Model and has been in the form of a simple spring.

Verification:

Inspection, Test

*Requirement Contact_4: Limit Circular Contact***Requirement:**

The Contact Model shall limit contact determination to surfaces that do not reside on the same vehicle or attached vehicles.

Rationale:

In order to avoid potential circular contact or attachments, which are not allowed in JEOD, surfaces residing on the same body or tree are excluded from contacting each other.

Verification:

Inspection, Test

*Requirement Contact_5: Contact Model Extensibility***Requirement:**

The Contact Model shall be extensible.

Rationale:

Other objects and classes should be able to derive from components of the Contact Model.

Verification:

Inspection

Chapter 3

Product Specification

3.1 Conceptual Design

The Contact Model was designed to provide a way for dynamic bodies to interact. This interaction is called “contact” since forces are applied when surfaces defined on those dynamic bodies interpenetrate. The uses for the Contact Model are many-fold, encompassing simple vehicle collisions to complex docking dynamics. In order to accommodate that range of use the Contact Model was designed with extension as an expectation.

Two basic considerations drove the design of the Contact Model. The first is that the Contact Model should be an extension of the Surface Model [5]. The second is that a user should only have to define the surfaces and interaction types (allowable pairs of surfaces) that will generate forces. The user is not required to define specific pairs of interacting surfaces but that can be done if desired.

3.2 Mathematical Formulations

3.2.1 Springs

The default force generation function included in the Contact Model is based on simple springs. This takes the form of

$$F = -kx - cv \tag{3.1}$$

Where k is the spring constant, x is displacement or penetration distance, c is the damping coefficient, and v is relative velocity.

3.2.2 Vector Calculations

The geometry calculations in the Contact Model rely on the Mathematical Functions Model [7] and the equations will not be repeated here. Most of the the vector equations are utilized in the Contact Model; including vector transforms, scaling, addition, and subtraction.

3.3 Interactions

3.3.1 Surface Model

As mentioned previously the Contact Model is an extension of the Surface Model [5]. Below is a listing of the Contact Model classes that are derived directly from Surface Model classes.

Base Surface Model Class	Derived Contact Model Class
InteractionFacet	ContactFacet
FacetParams	ContactParams
InteractionSurface	ContactSurface
InteractionFacetFactory	PointContactFacetFactory
InteractionFacetFactory	LineContactFacetFactory

In addition new classes were created in the Surface Model to support the special geometries required by the Contact Model. The FlatPlateCircular class is used to generate spherical contact surface about a point. The Cylinder class is used to generate a rod like structure with half spheres encasing the ends about a line.

3.4 Detailed Design

3.4.1 API

Follow this link for the [Contact Model API \[1\]](#).

3.4.2 Contact Class

The Contact class acts as a manager for the contact interaction and is a concept not seen in other extensions of the surface model such as aerodynamics and radiation pressure. The purpose of the Contact class is to construct a list, called `contact_pairs`, of `ContactPair` objects which link two `ContactFacet` objects together and calculates / stores the relative state between them. During run time the Contact class loops through this list so each pair of facets can be checked to see if contact has occurred.

The `Contact.contact_pairs` list is populated in two stages during initialization. Each `ContactFacet` object that registers with an instance of the Contact class creates a `ContactPair` object with itself as the subject but absent a target. After all contact facets are registered the Contact class method `Contact.initialize_contact` does a double loop through the incomplete contact pairs to construct new instances of the `ContactPair` class with both a subject and a target. Several checks are performed to determine if a pair of the two contact facets can be constructed. Since the `ContactPair` class is a pure virtual base class, as is the `ContactFacet` class, the first check is to determine if a derived class exists that can contain the specific types of contact facets. An additional check is performed by comparing each facets `ContactParam` type to the list of pair interactions that is also contained in the Contact class. If a `PairInteraction` object defining the interaction between the contact facets' parameter types doesn't exist then no pair is created.

At runtime the `Contact` class loops through the pairs contained in the `contact_pairs` list. After inquiring to ensure that the pair is complete (has a subject and target), active, and optionally that the facets are in range to interact the `Contact` class asks the contact pair to determine if contact has occurred.

3.4.3 ContactPair Class

The `ContactPair` class is a virtual base class, and its derived classes perform most of the work in the Contact Model. It is a `ContactPair` class that determines if and when two `ContactFacets` interact. The base class contains references to two contact facets, a subject and a target. It also contains a `RelativeDerivedState` object which is used to calculate and store the relative state between the subject and target `ContactFacets`. In addition each `ContactPair` contains a reference to a `PairInteraction` object that defines force calculation method in the event of contact. During initialization the `ContactPair` class constructs the relative state between its subject and target facets. During runtime the virtual method `in_contact` is used by all derived classes of the `ContactPair` class to determine if their subject and target are in contact with each other. If the `in_contact` method determines that contact has occurred then appropriate forces are generated using the `PairInteraction` associated with the `ContactPair`. All unique pairs of `ContactFacet` subclass types require a specific implementation of `ContactPair`. For example the Contact Model contains two derived classes extending the base `ContactFacet` class, but contains three `ContactPair` derived classes to deal with the possible pairings between these contact facets. Each derived `ContactFacet` class can interact with others of the same type which requires two distinct `ContactPair` implementations. For them to interact with each other we need a third `ContactPair` implementation.

3.4.4 ContactSurface Class

A contact surface is a collection of contact facets that are contained on the same dynamic body (`DynBody` [2]). It is where the forces generated on individual facets will be summed so they can all be applied to the dynamic body. As previously mentioned the `ContactSurface` class is a subclass of an `InteractionSurface` from the Surface Model [5], however the stipulation that it apply only to one `DynBody` instance is a limitation on the standard behavior associated with a surface as defined in the Surface Model.

3.4.5 ContactFacet Class

A contact facet must contain a reference to a dynamic body (`DynBody` [2]). At its most basic a contact facet is a vehicle point (`BodyRefFrame` [2]) on a specific dynamic body. From the position and normal of the vehicle point, the geometry of the specific type of facet is constructed and used by the `ContactPair` class to determine when a contact facet intersects another contact facet. During initialization specific derived classes of `ContactFacet` determine whether specific `ContactPairs` can be created. Extensibility of the types of surfaces available to the Contact Model is achieved by creating new types of contact facets. It is also necessary to create new `ContactPair` classes to define the interaction between the new contact facet and others of its type or any of the preexisting types of contact facets.

3.4.6 ContactParams Class

The ContactParams class add no new functionality to the base FacetParams class from the Surface Model [5]. The name associated with the parameters is used to match pairs of contact facets with the correct PairInteraction object.

3.4.7 PairInteraction Class

The PairInteraction class is a pure virtual base class and is intended to be extended to define multiple force calculation methods. Extensions of this class are expected to contain all the parameters they need to calculate contact forces. In addition, an inheriting class must define the pure virtual method calculate_forces which takes all relevant geometry information that it might need to calculate contact forces. The calculate_forces function is called from a contact pair once its geometry calculations have determined that contact between facets has occurred. Each simulation defined PairInteraction subclass must be registered with an instance of the Contact class. When Contact-Pair instances are created the ContactFacet ContactParams types must match with a registered PairInteraction or no pair is created. A reference to the a specific PairInteraction is stored in each successfully created ContactPair.

3.4.8 Springs

The default force generation parameters included in the Contact Model are based on simple springs, equation 3.1.

By default this spring force is designed to oppose the penetration of contact, but a sign reversal could invert this behavior making the spring forces applicable to simulations requiring latching.

3.5 Inventory

Table 3.1: Source Files

File Name
include/class_declarations.hh
include/contact.hh
include/contact_facet.hh
include/contact_messages.hh
include/contact_pair.hh
include/contact_params.hh
include/contact_surface.hh
include/contact_surface_factory.hh
include/contact_utils.hh

Continued on next page

Table 3.1: Source Files (continued from previous page)

File Name
include/contact_utils_inline.hh
include/line_contact_facet.hh
include/line_contact_facet_factory.hh
include/line_contact_pair.hh
include/line_point_contact_pair.hh
include/pair_interaction.hh
include/point_contact_facet.hh
include/point_contact_facet_factory.hh
include/point_contact_pair.hh
include/spring_pair_interaction.hh
src/cmake_file_list.cmake
src/contact.cc
src/contact_facet.cc
src/contact_messages.cc
src/contact_pair.cc
src/contact_params.cc
src/contact_surface.cc
src/contact_surface_factory.cc
src/line_contact_facet.cc
src/line_contact_facet_factory.cc
src/line_contact_pair.cc
src/line_point_contact_pair.cc
src/pair_interaction.cc
src/point_contact_facet.cc
src/point_contact_facet_factory.cc
src/point_contact_pair.cc
src/spring_pair_interaction.cc

Table 3.2: Documentation Files

File Name
docs/contact.pdf
docs/refman.pdf
docs/tex/abstract.tex
docs/tex/contact.bib

Continued on next page

Table 3.2: Documentation Files (continued from previous page)

File Name
docs/tex/contact.sty
docs/tex/contact.tex
docs/tex/guide.tex
docs/tex/intro.tex
docs/tex/ivv.tex
docs/tex/makefile
docs/tex/model_name.mk
docs/tex/reqt.tex
docs/tex/spec.tex

Table 3.3: Verification Files

File Name
verif/Contact_Modified_data/contact/contact_params.py
verif/Contact_Modified_data/contact/line_facet.py
verif/Contact_Modified_data/contact/pair_interaction.py
verif/Contact_Modified_data/contact/point_facet.py
verif/Contact_Modified_data/date_n_time/epoch.py
verif/Contact_Modified_data/mass/veh_mass.py
verif/Contact_Modified_data/mass/veh_mass_line.py
verif/Contact_Modified_data/state/integrator.py
verif/Contact_Modified_data/vehicle/sv_in_free.py
verif/Contact_S_modules/contact.sm
verif/Contact_S_modules/dynamics.sm
verif/Contact_S_modules/sv_collect_veh.sm
verif/Contact_S_modules/sv_dyn.sm
verif/Contact_S_modules/time.sm
verif/SIM_contact/Contact_Modified_data
verif/SIM_contact/Contact_S_modules
verif/SIM_contact/S_define
verif/SIM_contact/S_overrides.mk
verif/SIM_contact/DP_Product/DP_contact_T10.xml
verif/SIM_contact/DP_Product/DP_contact_forces
verif/SIM_contact/DP_Product/DP_states

Continued on next page

Table 3.3: Verification Files (continued from previous page)

File Name
verif/SIM_contact/DP_Product/DP_validation.xml
verif/SIM_contact/Log_data/log_contact_data.py
verif/SIM_contact/SET_test/RUN_line/input.py
verif/SIM_contact/SET_test/RUN_line_arbitrary/input.py
verif/SIM_contact/SET_test/RUN_line_inverse/input.py
verif/SIM_contact/SET_test/RUN_line_point/input.py
verif/SIM_contact/SET_test/RUN_line_side_to_side/input.py
verif/SIM_contact/SET_test/RUN_point/input.py
verif/SIM_contact/SET_test/RUN_point_inverse/input.py
verif/SIM_contact/SET_test/RUN_point_off_center/input.py
verif/SIM_contact/SET_test_val/RUN_line/input.py
verif/SIM_contact/SET_test_val/RUN_line/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_line/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_line_arbitrary/input.py
verif/SIM_contact/SET_test_val/RUN_line_arbitrary/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_line_arbitrary/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_line_inverse/input.py
verif/SIM_contact/SET_test_val/RUN_line_inverse/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_line_inverse/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_line_point/input.py
verif/SIM_contact/SET_test_val/RUN_line_point/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_line_point/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_line_side_to_side/input.py
verif/SIM_contact/SET_test_val/RUN_line_side_to_side/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_line_side_to_side/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_point/input.py
verif/SIM_contact/SET_test_val/RUN_point/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_point/log_contact_data.trk
verif/SIM_contact/SET_test_val/RUN_point_inverse/input.py
verif/SIM_contact/SET_test_val/RUN_point_inverse/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_point_inverse/log_contact_data.trk

Continued on next page

Table 3.3: Verification Files (continued from previous page)

File Name
verif/SIM_contact/SET_test_val/RUN_point_off_center/input.py
verif/SIM_contact/SET_test_val/RUN_point_off_center/log_contact_data.header
verif/SIM_contact/SET_test_val/RUN_point_off_center/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_line/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_line/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_line/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_line_arbitrary/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_line_arbitrary/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_line_arbitrary/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_line_inverse/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_line_inverse/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_line_inverse/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_line_point/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_line_point/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_line_point/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_line_side_to_side/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_line_side_to_side/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_line_side_to_side/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_point/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_point/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_point/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_point_inverse/input.py
verif/SIM_contact/SET_test_val_rh8/RUN_point_inverse/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_point_inverse/log_contact_data.trk
verif/SIM_contact/SET_test_val_rh8/RUN_point_off_center/input.py

Continued on next page

Table 3.3: Verification Files (continued from previous page)

File Name
verif/SIM_contact/SET_test_val_rh8/RUN_point_off_center/log_contact_data.header
verif/SIM_contact/SET_test_val_rh8/RUN_point_off_center/log_contact_data.trk
verif/SIM_ground_contact/Contact_Modified_data
verif/SIM_ground_contact/Contact_S_modules
verif/SIM_ground_contact/S_define
verif/SIM_ground_contact/S_overrides.mk
verif/SIM_ground_contact/Log_data/log_contact_data.py
verif/SIM_ground_contact/Modified_data/ground/ground_facet.py
verif/SIM_ground_contact/Modified_data/ground/pair_interaction.py
verif/SIM_ground_contact/Modified_data/vehicle/sv_earth.py
verif/SIM_ground_contact/SET_test/RUN_contact_ground/input.py
verif/SIM_ground_contact/SET_test_val/RUN_contact_ground/input.py
verif/SIM_ground_contact/SET_test_val/RUN_contact_ground/log_contact_data.header
verif/SIM_ground_contact/SET_test_val/RUN_contact_ground/log_contact_data.trk
verif/SIM_ground_contact/SET_test_val_rh8/RUN_contact_ground/input.py
verif/SIM_ground_contact/SET_test_val_rh8/RUN_contact_ground/log_contact_data.header
verif/SIM_ground_contact/SET_test_val_rh8/RUN_contact_ground/log_contact_data.trk
verif/SIM_ground_contact/S_modules/contact.sm
verif/SIM_ground_contact/S_modules/environment.sm
verif/SIM_ground_contact/S_modules/planet.sm
verif/SIM_ground_contact/S_modules/sv_dyn.sm
verif/SIM_ground_contact/models/contact_ground/include/contact_ground.hh
verif/SIM_ground_contact/models/contact_ground/include/ground_facet.hh
verif/SIM_ground_contact/models/contact_ground/include/ground_interaction.hh
verif/SIM_ground_contact/models/contact_ground/include/line_ground_interaction.hh

Continued on next page

Table 3.3: Verification Files (continued from previous page)

File Name
verif/SIM_ground_contact/models/contact_ground/include/point_ground_interaction.hh
verif/SIM_ground_contact/models/contact_ground/src/contact_ground.cc
verif/SIM_ground_contact/models/contact_ground/src/ground_facet.cc
verif/SIM_ground_contact/models/contact_ground/src/ground_interaction.cc
verif/SIM_ground_contact/models/contact_ground/src/line_ground_interaction.cc
verif/SIM_ground_contact/models/contact_ground/src/point_ground_interaction.cc
verif/SIM_ground_contact/models/terrain/include/terrain.hh
verif/SIM_ground_contact/models/terrain/include/terrain_radius.hh
verif/SIM_ground_contact/models/terrain/src/terrain.cc
verif/SIM_ground_contact/models/terrain/src/terrain_radius.cc

Chapter 4

User Guide

4.1 Instructions for Simulation Users

4.1.1 General Description

The verification simulation SIM_contact_T10 and its associated input files are used in the examples below. They demonstrate the use of the Contact Model with a Trick 10 series simulation executive. The simulation SIM_contact contains an example of using the Contact Model with a Trick 7 series simulation executive.

4.1.2 Pair Interactions

Central to having surfaces actually contact each other is the creation of instances of the Pair_Interaction class. Each such object links two instances of Contact_Params by name.

```
execfile( "Contact_Modified_data/contact/pair_interaction.py")
set_contact_interaction(contact)
```

As seen below a pair interaction contains the names of the parameters that will produce interaction as well as the values need to calculated forces from the contact should it occur. In this example we are using the Contact Model provided spring model, so we define the spring constant (spring_k), damping coefficient (damping.b), and the coefficient of friction (mu).

```
def set_contact_interaction(contact_reference) :

    pair_interaction_local = trick.SpringPairInteraction()
    pair_interaction_local.thisown = 0

    pair_interaction_local.params_1 = "steel"
    pair_interaction_local.params_2 = "steel"

    pair_interaction_local.spring_k = trick.attach_units( "lbf/in",20.0)
```

```

pair_interaction_local.damping_b = trick.attach_units( "lbf*s/in",0.4)
pair_interaction_local.mu = 0.05

contact_reference.contact.register_interaction(pair_interaction_local)

return

```

4.1.3 Contact Parameters

All vehicles in the SET_test runs contained in SIM_contact_T10 use the same contact parameters. The inclusion of contact parameters takes the following form.

```

execfile( "Contact_Modified_data/contact/contact_params.py")
set_contact_params(veh1_dyn)

```

Contact parameters are purposely very simple and are used to control the types of possible interactions. In this case all contact facets will have parameters of the name “steel” and they have the potential for contact if there exists an instance of the Pair_Interaction class that defines a “steel” on “steel” interaction like the example above. Creating and naming an instance of the ContactParams class is show below.

```

def set_contact_params(sv_dyn_reference) :

    contact_params_local = trick.ContactParams()
    contact_params_local.thisown = 0

    contact_params_local.name = "steel"

    sv_dyn_reference.facet_params = contact_params_local
    sv_dyn_reference.contact_surface_factory.add_facet_params(contact_params_local)

    return

```

4.1.4 Contact Surface and Facets

Now that there are contact parameters available to be associated with the contact facets and defined pair interactions to generate valid pairings between them, the contact facets are constructed.

```

execfile( "Contact_Modified_data/contact/point_facet.py")
set_contact_point_facet(veh1_dyn, "veh1")

```

This is an example of adding one facet. However, implementing multiple facets would only involve modifying the python function to accept more parameters for the position, normal, parameter name, etc. The type of facet being created below is of the FlatPlateCircular class, so in addition

to the required fields of “name,” “position” and “param_name” you must also specify the “normal” and “radius.” Since this facet is intended for use in the Contact Model a “mass_body_name” must also be specified, and in this case the associated mass_body shares the same name as the surface_model.struct_body_name.

```
def set_contact_point_facet(sv_dyn_reference, SV_NAME) :

    exec('sv_dyn_reference.surface_model.struct_body_name = '' + SV_NAME + ''')

    fp = trick.FlatPlateCircular()
    fp.thisown = 0

    exec( 'fp.name = '' + SV_NAME + '_facet''')
    fp.position = trick.attach_units( "m",[ 0.0 , 0.0, 0.0 ])
    fp.normal = [ 1.0 , 0.0 , 0.0 ]
    fp.radius = trick.attach_units( "m",1.0)
    fp.param_name = "steel"
    exec('fp.mass_body_name = '' + SV_NAME + ''')

    sv_dyn_reference.facet_ptr = fp
    sv_dyn_reference.surface_model.add_facet(fp)

    return
```

4.1.5 Logging

Logging the internal details of the Contact Model, such as the forces a specific facets, is difficult due to the number of base class pointer references to derived classes. However, it is straightforward to log the forces and torques collected by contact on the entire contact surface.

```
def log_contact_data ( log_cycle ) :
    # Import the JEOD logger
    import sys
    import os
    sys.path.append ('/'.join([os.getenv("JEOD_HOME"), "lib/jeod/python"]))
    import jeod_log

    # Create the logger.
    logger = jeod_log.Logger (data_record.drd)

    logger.open_group (1, "contact_data")

    logger.log_scalar(
        ("veh1_dyn.body.composite_properties.mass",
         "veh2_dyn.body.composite_properties.mass"))
```

```

logger.log_vector(
    ("veh1_dyn.body.composite_body.state.trans.position",
     "veh1_dyn.body.composite_body.state.trans.velocity",
     "veh1_dyn.contact_surface.contact_force",
     "veh1_dyn.contact_surface.contact_torque",
     "veh2_dyn.body.composite_body.state.trans.position",
     "veh2_dyn.body.composite_body.state.trans.velocity",
     "veh2_dyn.contact_surface.contact_force",
     "veh2_dyn.contact_surface.contact_torque"))

logger.close_group()

```

4.2 Instruction for Simulation Developers

The examples given in this sections come from the S_define for SIM_contact_T10 and describe the use of the Contact Model with Trick 10 simulation executive.

4.2.1 Vehicle Simulation Object Additions

The majority of the definitions and jobs needed for the Contact Model are best placed in the simulation objects for the vehicles. In general each vehicle will contain its own unique instance of the SurfaceModel class which will contain all the facets and parameters associated with the vehicle. The following lines set up an instance of the SurfaceModel class and a pointer to add facet parameters to it.

```

SurfaceModel          surface_model;
FacetParams           * facet_params;

```

Then it is time to instantiate a ContactSurface object and a factory to create it.

```

ContactSurface         contact_surface;
ContactSurfaceFactory  contact_surface_factory;

```

This is followed by the definition of several variables needed by the initialization routines and the input file. There is a facet pointer which is used to add facets to SurfaceModel. There are also pre-declarations of the types of contact facets that will be created in the simulation input files, contact parameters and a specific type of pair interaction.

```

FlatPlateCircular      * flat_plate_circular;
Cylinder               * cylinder;
ContactParams * contact_params;
SpringPairInteraction * spring_pair_interaction;
Facet * facet_ptr;
unsigned int integer;

```


Next we get to the initialization jobs that should occur in the following order in the S_define:

- `SurfaceModel.initialize_mass_connections` - creates the linkage between a Facet and a Mass or in the case of the Contact Model, a facet and a dynamics body,
- `ContactSurfaceFactory.create_surface` - creates a `ContactSurface` from the `Surface` base class, which means that it creates a `ContactFacet` from the information contained in each `Facet` base class,
- `ContactManager.register_contact` - registers a set of contact facets with the contact manager, with the easiest way being to use the array of contact facets in the contact surface,

```
P_BODY ("initialization") surface_model.initialize_mass_connections(  
    internal_dynamics->dyn_manager );  
P_BODY ("initialization") contact_surface_factory.create_surface(  
    & surface_model,  
    & contact_surface);  
P_BODY ("initialization") internal_contact->contact.register_contact(  
    contact_surface.contact_facets,  
    contact_surface.facets_size);
```

The only recurring job in the vehicle simulation object from the contact model is a call to `collect_forces_torques` in each contact surface. This collects forces and torques from every contact facet associated with the contact surface and sums them to produce the total forces from contact.

```
P_DYN ("derivative") contact_surface.collect_forces_torques();
```

4.2.2 Contact Simulation Object

Unlike some of the other Surface Model derived interaction models, the Contact Model requires a separate manager to track the contact facets so a determination of contact forces can be accomplished. The basic form of this simulation object will contain an instance of the `Contact` class. This manager object should be initialized after all the vehicles have completed the registration of their contact surfaces. It is the function `Contact.initialize_contact` that creates pairs based on the contact facets, parameters, and pair interactions that have been registered with the manager. The call to the method `check_contact` is the main driver for the entire Contact Model. It is this function that begins the process of determining if contact has occurred during runtime.

```
##include "interactions/contact/include/contact.hh"
```

```
class ContactSimObject: public Trick::SimObject {
```

```
    public:  
        Contact contact;
```

```
// Instances for matching to other sim objects:
```

```

    DynamicsSimObject * internal_dynamics;

//Constructor
ContactSimObject(
    DynamicsSimObject & ext_dynamics) {

    internal_dynamics = & ext_dynamics;

    P_DYN ("initialization") contact.initialize_contact(
        & internal_dynamics->dyn_manager);
    //
    // Derivative class jobs
    //
    P_DYN ("derivative") contact.check_contact();
}

private:
    ContactSimObject (const ContactSimObject&);
    ContactSimObject & operator = (const ContactSimObject&);

};
ContactSimObject contact(dynamics);

```

4.3 Instruction for Model Developers

The Contact Model was designed with the expectation of user extension. Some extensions such as adding new types of contact facets or new pair interactions are relatively easy. Some such as extending the contact base class to include a completely new concept such as latching or ground contact may be challenging depending on the complexity desired.

4.3.1 Pair Interactions

The virtual base class for interaction and force generation in the Contact Model is called PairInteraction. This class contains a pure virtual function, called force_torque, used to calculate the forces and torques a specific facet produces when in contact. This method takes in information determined from the geometry of the interacting facets, but not knowledge of the specific facet geometries. In the released version of the Contact Model, one derived class of PairInteraction is included which is the SpringPairInteraction class. This basic functionality applies forces and torques assuming that the facets resist inter-penetration using the dynamics of simple springs. The PairInteraction class can be extended to simulate whatever force generation dynamics the user desires.

4.3.2 Contact Facets

It is possible to add new types of contact facets to the Contact Model. All types of contact facets are derived from the base class `ContactFacet`. To add a new type it is necessary to create a new class derived from `ContactFacet`. Then one must create a matching `ContactFacetFactory` for the new type of `ContactFacet`. If the new type of `ContactFacet` can be defined by the geometry of an existing facet in the Surface Model, then there is no need to create a matching facet there. If not, a new derived class of the Surface Model Facet class will need to be created in the Surface Model [5]. For example the `PointContactFacet` makes use of the Surface Model class `CircularFlatPlate` as its base. A `CircularFlatPlate` contains a point and normal, but unlike a `FlatPlate` it also contains a radius which can be used as the interaction distance needed to properly define a `PointContactFacet`.

Now that a new type of `ContactFacet` has been created it is necessary to define how it will interact with types that already exist if you want contact to occur between those contact facets. Unless this is done a `ContactPair` between the new type and old will not be created by the `Contact` class, which can be a good way to limit list size and control the resource use of the Contact Model.

4.3.3 Contact

The manager class, called `Contact`, is also designed with extension in mind. This JEOD release contains an example of such an extension in `SIM_ground_contact` located in the `verif` directory of Contact Model. This simulation includes two new models. One is a simple radius of the planet base terrain model called “terrain”. The other called “contact_ground” is an extension of the Contact Model to include contact between vehicle facets and the surface of a planet. The treatment of the ground contact problem in this example simulation and contact ground model is merely demonstrative, for it assumes a non rotating earth, contact at the radius of the planet, and other simplifications. However, it does give a powerful demonstration of the extensibility of the Contact Model.

Chapter 5

Inspections, Tests, and Metrics

5.1 Inspections

Inspection Contact_1: Top-level inspection

This document structure, the code, and associated files have been inspected, and together satisfy requirement [Contact_1](#).

Inspection Contact_2: Extensibility inspection

Examples of the extensibility of the Contact Model are numerous in the released version of JEOD and [Contact_5](#) is easily verified.

- The Contact class is extended for ground contact in the example simulation SIM_ground_contact_T10.
- The SpringPairInteraction class is an extension of the PairInteraction class.
- The PointContactFacet class and the LineContactFacet class extend the ContactFacet class.

Inspection Contact_3: Circular contact inspection

The code was inspected and used in non-JEOD released simulations and the non-circular nature of the Contact Model was verified. [Contact_4](#).

5.2 Tests

Test Contact_1: Two-Sphere Contact: Aligned

Purpose:

The purpose of this test is to see the results of two point contact facets contacting and

rebounding. For this test the contact facets were aligned (no translation or rotation offsets) along the line of approach.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_point

Requirements:

By passing this test, the Contact Model partially satisfies requirements **Contact_2** and **Contact_3**.

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_2: Two-Sphere Contact: Inversed

Purpose:

The purpose of this test is to see the results of two point contact facets contacting and rebounding. For this test the contact facets were rotated 180 degrees about line of approach, but had not translational offset about that line.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_point_inverse

Requirements:

By passing this test, the Contact Model partially satisfies requirements **Contact_2** and **Contact_3**.

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_3: Two-Sphere Contact: Off Center

Purpose:

The purpose of this test is to see the results of two point contact facets contacting and rebounding. For this test the contact facets were rotated 180 degrees about and translationally offset from the line of approach.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_point_off_center

Requirements:

By passing this test, the Contact Model partially satisfies requirements **Contact_2** and **Contact_3**.

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_4: Two-Cylinder Contact: Aligned

Purpose:

The purpose of this test is to see the results of two line contact facets contacting and rebounding. For this test the contact facets were aligned (no translation or rotation offsets) along the line of approach.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_line

Requirements:

By passing this test, the Contact Model partially satisfies requirements **Contact_2** and **Contact_3**.

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_5: Two-Cylinder Contact: Inverse

Purpose:

The purpose of this test is to see the results of two line contact facets contacting and rebounding. For this test the contact facets were rotated 180 degrees about the line of approach.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_line_inverse

Requirements:

By passing this test, the Contact Model partially satisfies requirements **Contact_2** and **Contact_3**.

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_6: Two-Cylinder Contact: Arbitrary

Purpose:

The purpose of this test is to see the results of two line contact facets contacting and rebounding. For this test the contact facets were rotated at arbitrary angles about and translationally offset from the line of approach.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_line_arbitrary

Requirements:

By passing this test, the Contact Model partially satisfies requirements [Contact_2](#) and [Contact_3](#).

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

Test Contact_7: Sphere Cylinder Contact

Purpose:

The purpose of this test is to see the results of a point contact facet and a line contact facet contacting and rebounding.

SIM directory: models/interactions/contact/verif/SIM_contact_T10

Run directory: RUN_line_point

Requirements:

By passing this test, the Contact Model partially satisfies requirements [Contact_2](#) and [Contact_3](#).

Procedure:

In this test, the simulation was run and the position, velocity, and contact forces of the two bodies was examined. The principle test being that the facets make contact at the appropriate range and produce forces in the correct directions.

Results:

The contact occurred at the correct distance. The two bodies then separated and the forces generated were equal and opposite.

5.3 Requirements Traceability

Requirement	Inspection or test
Contact_1 - Top-level requirements	Insp. Contact_1 - meets Top-level
Contact_2 - Contact Between Surfaces in 3D Space	All tests
Contact_3 - Default Spring Contact Force	All tests
Contact_4 - Limit Circular Contact	Insp. Contact_3
Contact_5 - Contact Model Extensibility	Insp. Contact_2

Table 5.1: Requirements Traceability

5.4 Metrics

Table 5.2: Coarse Metrics

File Name	Number of Lines			
	Blank	Comment	Code	Total
include/class_declarations.hh	18	61	28	107
include/contact.hh	29	106	41	176
include/contact_facet.hh	30	121	37	188
include/contact_messages.hh	23	95	22	140
include/contact_pair.hh	30	104	34	168
include/contact_params.hh	15	68	17	100
include/contact_surface.hh	23	86	29	138
include/contact_surface_ factory.hh	20	83	25	128
include/contact_utils.hh	13	66	13	92
include/contact_utils_inline.hh	33	93	191	317
include/line_contact_facet.hh	23	79	29	131
include/line_contact_facet_ factory.hh	20	70	25	115
include/line_contact_pair.hh	21	76	22	119
include/line_point_contact_ pair.hh	21	77	22	120
include/pair_interaction.hh	22	89	27	138
include/point_contact_ facet.hh	24	85	29	138
include/point_contact_facet_ factory.hh	20	70	25	115
include/point_contact_pair.hh	21	76	22	119
include/spring_pair_ interaction.hh	21	78	25	124
src/cmake_file_list.cmake	2	0	22	24
src/contact.cc	39	84	149	272
src/contact_facet.cc	20	34	44	98
src/contact_messages.cc	20	29	11	60
src/contact_pair.cc	23	60	57	140
src/contact_params.cc	12	32	9	53
src/contact_surface.cc	39	66	97	202
src/contact_surface_factory.cc	31	57	129	217
src/line_contact_facet.cc	34	73	130	237

Continued on next page

Table 5.2: Coarse Metrics (continued from previous page)

File Name	Number of Lines			
	Blank	Comment	Code	Total
src/line_contact_facet_ factory.cc	27	50	76	153
src/line_contact_pair.cc	33	60	73	166
src/line_point_contact_pair.cc	32	57	71	160
src/pair_interaction.cc	12	38	16	66
src/point_contact_facet.cc	26	68	72	166
src/point_contact_facet_ factory.cc	26	50	75	151
src/point_contact_pair.cc	23	48	52	123
src/spring_pair_interaction.cc	21	64	51	136
Total	847	2453	1797	5097

Table 5.3: Cyclomatic Complexity

Method	File	Line	ECC
jeod::std::get_name ()	include/contact_facet.hh	171	1
jeod::ContactUtils::create_ relstate_name (char * name1, char * name2, char ** out_str)	include/contact_utils_inline.hh	86	1
jeod::ContactUtils::dist_line_ segments (double p1[3], double p2[3], double p3[3], double p4[3], double * pa, double * pb)	include/contact_utils_inline.hh	112	21
jeod::Contact::Contact ()	src/contact.cc	50	1
jeod::Contact::~~Contact ()	src/contact.cc	62	3
jeod::Contact::check_contact ()	src/contact.cc	82	6
jeod::Contact::initialize_ contact (DynManager * manager)	src/contact.cc	102	8
jeod::Contact::unique_pair (const ContactFacet * facet_1, const ContactFacet * facet_2)	src/contact.cc	140	6
jeod::Contact::register_ contact (ContactFacet * facet)	src/contact.cc	162	2
jeod::Contact::register_ contact (ContactFacet ** facets, unsigned int n Facets)	src/contact.cc	178	2
jeod::Contact::register_ contact (ContactFacet * facet1, ContactFacet * facet2)	src/contact.cc	192	3
jeod::Contact::register_ contact (ContactFacet ** facets1, unsigned int n Facets1, ContactFacet ** facets2, unsigned int n Facets2)	src/contact.cc	212	3

Continued on next page

Table 5.3: Cyclomatic Complexity (continued)

Method	File	Line	ECC
jeod::Contact::register_ interaction (PairInteraction * interaction)	src/contact.cc	236	1
jeod::Contact::find_interaction (ContactParams * params_ 1, ContactParams * params_2)	src/contact.cc	245	3
jeod::ContactFacet::create_ vehicle_point ()	src/contact_facet.cc	46	2
jeod::ContactPair::in_range ()	src/contact_pair.cc	45	3
jeod::ContactPair::is_active ()	src/contact_pair.cc	60	4
jeod::ContactPair::is_complete ()	src/contact_pair.cc	73	2
jeod::ContactPair::get_subject ()	src/contact_pair.cc	86	1
jeod::ContactPair::get_target ()	src/contact_pair.cc	95	1
jeod::ContactPair::check_tree ()	src/contact_pair.cc	104	2
jeod::ContactPair::initialize_ relstate (DynManager * dyn_manager)	src/contact_pair.cc	124	1
jeod::ContactParams::Contact Params ()	src/contact_params.cc	39	1
jeod::ContactSurface::JEOD_ DECLARE_ATTRIBUTES (ContactFacet)	src/contact_surface.cc	51	1
jeod::ContactSurface::~~ ContactSurface ()	src/contact_surface.cc	61	1
jeod::ContactSurface:: allocate_array (unsigned int size)	src/contact_surface.cc	75	3
jeod::ContactSurface:: allocate_interaction_facet (Facet * facet, Interaction FacetFactory * factory, FacetParams * params, unsigned int index)	src/contact_surface.cc	108	4

Continued on next page

Table 5.3: Cyclomatic Complexity (continued)

Method	File	Line	ECC
jeod::ContactSurface::collect_forces_torques ()	src/contact_surface.cc	177	2
jeod::ContactSurfaceFactory::ContactSurfaceFactory ()	src/contact_surface_factory.cc	45	1
jeod::ContactSurfaceFactory::create_surface (Surface Model * surface, Interaction Surface * inter_surface)	src/contact_surface_factory.cc	65	13
jeod::ContactSurfaceFactory::add_facet_params (Facet Params * to_add)	src/contact_surface_factory.cc	168	3
jeod::LineContactFacet::LineContactFacet ()	src/line_contact_facet.cc	49	1
jeod::LineContactFacet::create_pair ()	src/line_contact_facet.cc	58	1
jeod::LineContactFacet::create_pair (ContactFacet * target, Contact * contact)	src/line_contact_facet.cc	75	6
jeod::LineContactFacet::calculate_contact_point (double nvec[3])	src/line_contact_facet.cc	154	4
jeod::LineContactFacet::set_max_dimension ()	src/line_contact_facet.cc	199	1
jeod::LineContactFacet::calculate_torque (double * tmp_force)	src/line_contact_facet.cc	207	1
jeod::LineContactFacetFactory::JEOD_DECLARE_ATTRIBUTES (LineContactFacet)	src/line_contact_facet_factory.cc	46	1
jeod::LineContactFacetFactory::create_facet (Facet * facet, FacetParams * params)	src/line_contact_facet_factory.cc	65	4
jeod::LineContactFacetFactory::is_correct_factory (Facet * facet)	src/line_contact_facet_factory.cc	135	2
jeod::LineContactPair::in_contact ()	src/line_contact_pair.cc	45	2

Continued on next page

Table 5.3: Cyclomatic Complexity (continued)

Method	File	Line	ECC
jeod::LineContactPair:: initialize_pair (Contact Facet * subject_facet, ContactFacet * target_ facet)	src/line_contact_pair.cc	132	2
jeod::LinePointContactPair:: in_contact ()	src/line_point_contact_pair.cc	46	2
jeod::LinePointContactPair:: initialize_pair (Contact Facet * subject_facet, ContactFacet * target_ facet)	src/line_point_contact_pair.cc	126	2
jeod::PairInteraction::is_ correct_interaction (Contact Params * subject_params, ContactParams * target_ params)	src/pair_interaction.cc	43	5
jeod::PointContactFacet:: PointContactFacet ()	src/point_contact_facet.cc	47	1
jeod::PointContactFacet:: create_pair ()	src/point_contact_facet.cc	55	1
jeod::PointContactFacet:: create_pair (ContactFacet * target, Contact * contact)	src/point_contact_facet.cc	72	3
jeod::PointContactFacet:: calculate_contact_point (double nvec[3])	src/point_contact_facet.cc	114	1
jeod::PointContactFacet::set_ max_dimension ()	src/point_contact_facet.cc	128	1
jeod::PointContactFacet:: calculate_torque (double * tmp_force)	src/point_contact_facet.cc	136	1
jeod::PointContactFacet Factory::JEOD_DECLAR E_ATTRIBUTES (Point ContactFacet)	src/point_contact_facet_ factory.cc	46	1
jeod::PointContactFacet Factory::create_facet (Facet * facet, FacetParams * params)	src/point_contact_facet_ factory.cc	64	4

Continued on next page

Table 5.3: Cyclomatic Complexity (continued)

Method	File	Line	ECC
jeod::PointContactFacet Factory::is_correct_factory (Facet * facet)	src/point_contact_facet_ factory.cc	133	2
jeod::PointContactPair::in_ contact ()	src/point_contact_pair.cc	44	2
jeod::PointContactPair:: initialize_pair (Contact Facet * subject_facet, ContactFacet * target_ facet)	src/point_contact_pair.cc	90	2
jeod::SpringPairInteraction:: calculate_forces (Contact Facet * subject, Contact Facet * target, Relative DerivedState * rel_state, double * penetration_ vector, double * rel_ velocity)	src/spring_pair_interaction.cc	46	2

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