SOFA: a modular yet efficient physical simulation architecture

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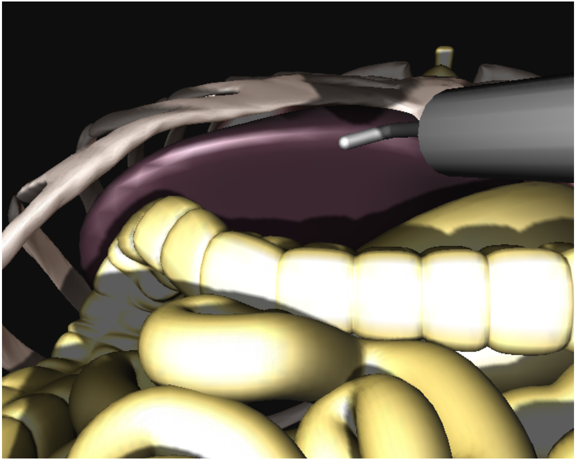
Outline

A complex physical simulation



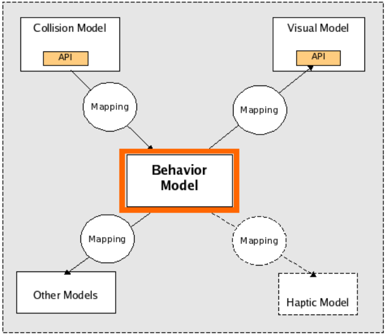
Material, internal forces, contraints, contact detection and modeling, ODE solution, visualization, interaction, etc.

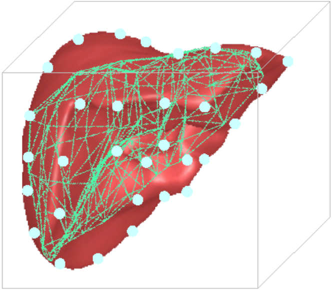
Simulation platforms

- Current platforms (ODE, Havok, Novodex, etc.) provide :
  - limited number of material types
  - limited number of geometry types
  - no control on collision detection algorithms
  - no control on interaction modeling
  - few (if any) control of the numerical models and methods.
  - no control on the main loop
  - few (if any) parallelism
- We need much more !
  - models, algorithms, scheduling, visualization, etc.

A generic approach

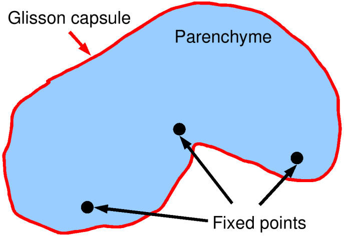
- Behavior model : all internal laws
- Others : interaction with the world
- Mappings : relations between the models (uni- or bi-directional)





Animation of a simple body

- a liver



- inside : soft material
- surface : stiffer material

A specialized program :

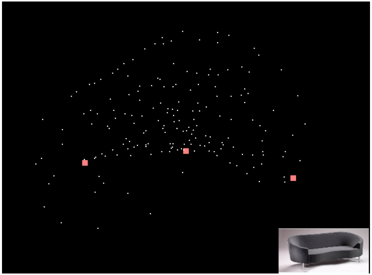
```
f  =  M*g
f  +=  F1(x,v)
f  +=  F2(x,v)
a  =  f/M
a  =  C(a)
v  +=  a * dt
x  +=  v * dt
display(x)
```

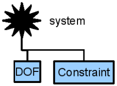
Outline

Components

Data :

- sample points and associated values : x, v, a, f
- constraints : fixed points
  other : oscillator, collision plane, etc.

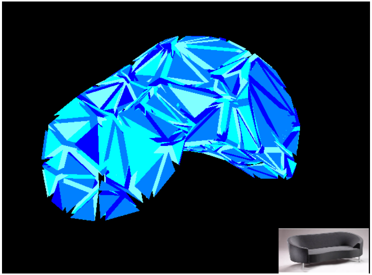


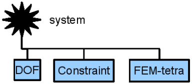


Components

Data :

- sample points and associated values : x, v, a, f
- constraints : fixed points
- force field : tetrahedron FEM
  other : triangle FEM, springs, Lennard-Jones, SPH, etc.





Components

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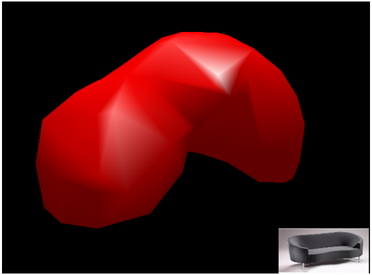
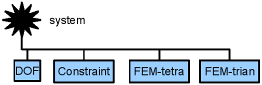
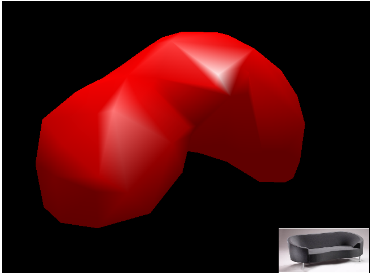


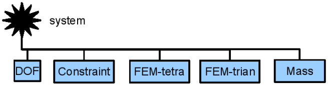


Components

Data :

- sample points and associated values : x, v, a, f
- constraints : fixed points
- force field : tetrahedron FEM
- force field : triangle FEM
- mass : uniform
  other : diagonal, sparse symmetric matrix

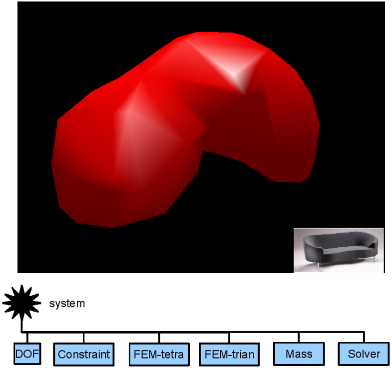




Components

Data :

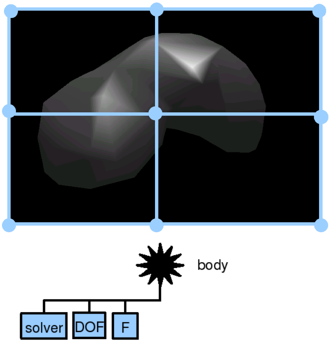
- sample points and associated values : x, v, a, f
- constraints : fixed points
- force field : tetrahedron FEM
- force field : triangle FEM
- mass : uniform
- ODE solver : explicit Euler *other : Runge-Kutta, implicite Euler, static solution, etc.*



Outline

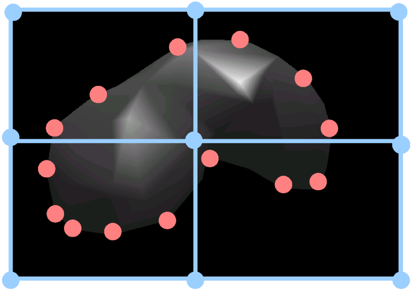
Layered body

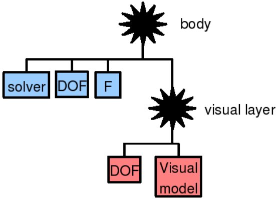
- independent DOFs (blue)



Layered body

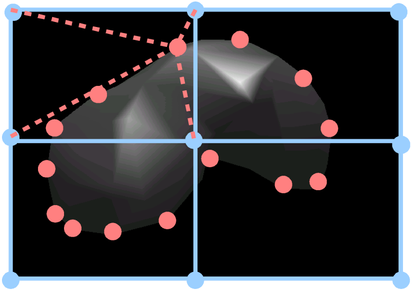
- independent DOFs (blue)
- visual samples (salmon)

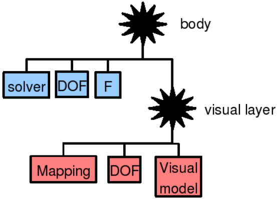




Layered body

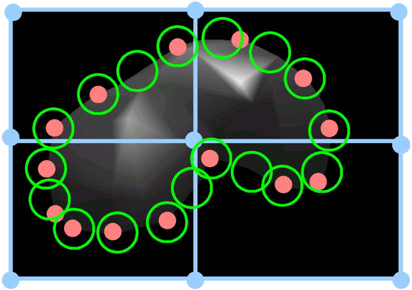
- independent DOFs (blue)
- visual samples (salmon)
- visual mapping

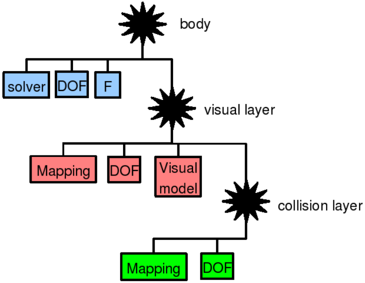




Layered body

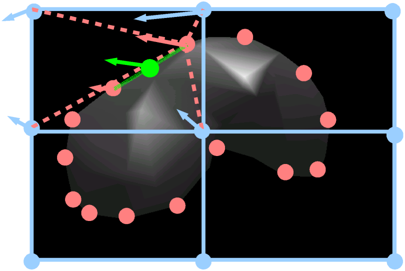
- independent DOFs (blue)
- visual samples (salmon)
- visual mapping
- collision samples (green)
- collision mapping





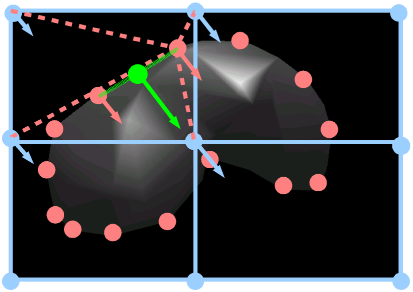
Layered body

- independent DOFs (blue)
- visual samples (salmon)
- visual mapping
- collision samples (green)
- collision mapping
- apply displacements
  1. $v_{visual} = J_{visual} v$
  2. $v_{collision} = J_{collision} v_{visual}$



Layered body

- independent DOFs (blue)
- visual samples (salmon)
- visual mapping
- collision samples (green)
- collision mapping
- apply displacements
  1. $v_{visual} = J_{visual} v$
  2. $v_{collision} = J_{collision} v_{visual}$
- apply forces
  1. $f_{visual} = J_{collision}^T f_{collision}$
  2. $f = J_{visual}^T f_{visual}$



More on mappings

- Map a set of degrees of freedom (the parent) to another (the child).
- Typically used to attach a geometry to control points.
- Child degrees of freedom (DOF) are not independent : their positions are totally defined by their parent's.
- Displacements are propagated top-down (parent to child) : $v_{child} = Jv_{parent}$
- Forces are propagated bottom-up

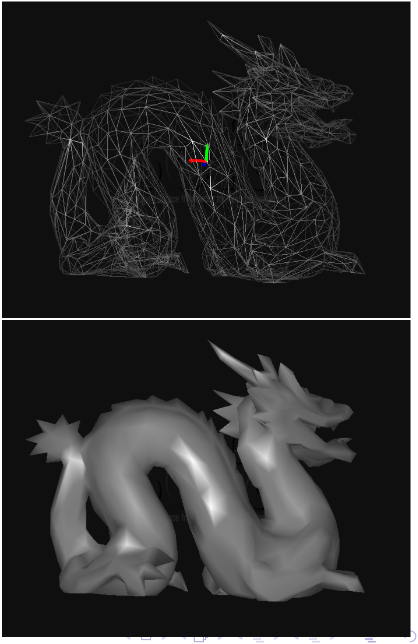
The physics of mappings

Example : line mapping

$$\begin{aligned} v = \begin{pmatrix} a & b \end{pmatrix} \begin{pmatrix} v_1 \\ v_2 \end{pmatrix} &= Jv \\ \begin{pmatrix} f_1 \\ f_2 \end{pmatrix} = \begin{pmatrix} a \\ b \end{pmatrix} f &= J^T f \end{aligned}$$

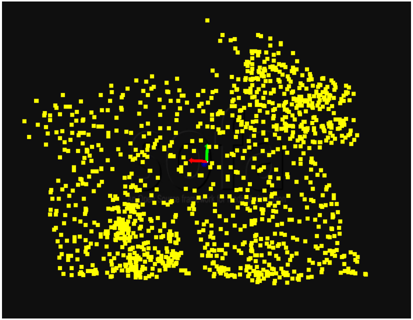
Examples of mappings

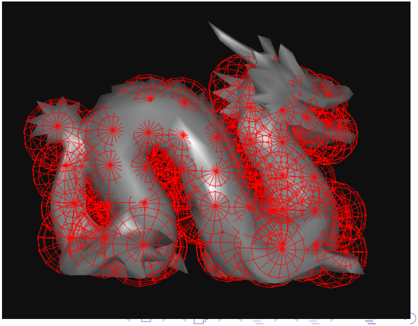
- RigidMapping can be used to attach points to a rigid body
  - to attach a visual model



Examples of mappings

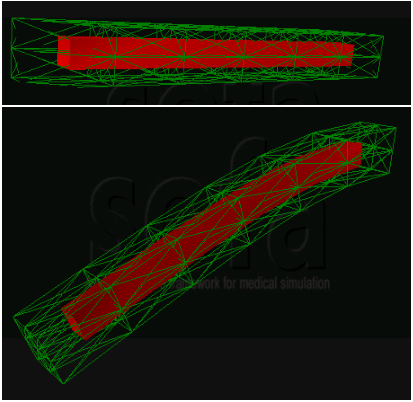
- RigidMapping can be used to attach points to a rigid body
  - to attach collision surfaces





Examples of mappings

- RigidMapping can be used to attach points to a rigid body
- BarycentricMapping can be used to attach points to a deformable body
  - to attach a visual model



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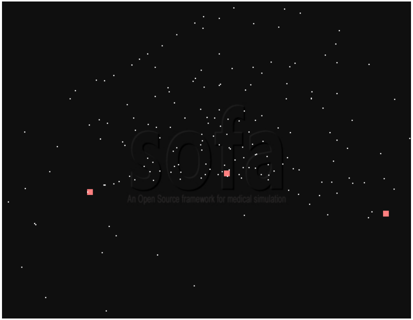
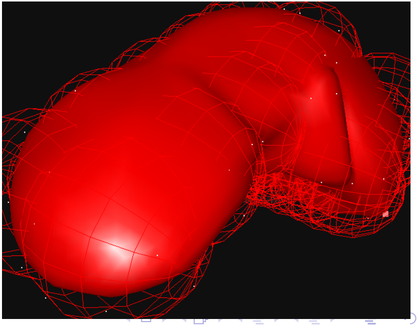
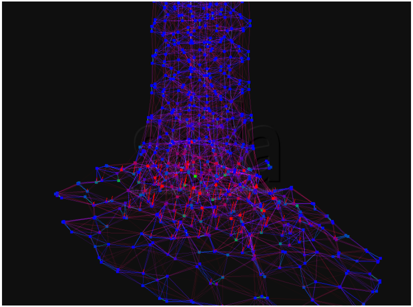
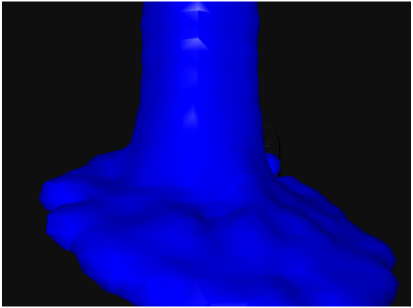




Examples of mappings

- RigidMapping can be used to attach points to a rigid body
- BarycentricMapping can be used to attach points to a deformable body
- More advanced mapping can be applied to fluids





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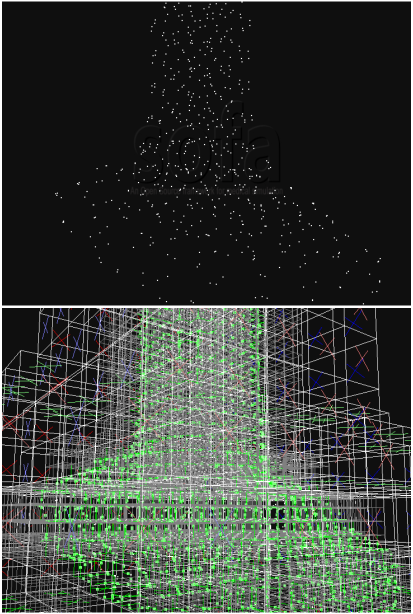


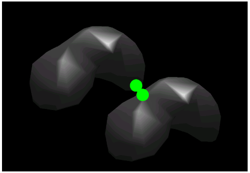
On the physical consistency of mappings

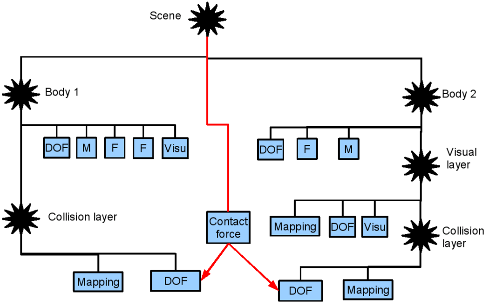
- Conservation of energy :
  Necessary condition : $v_{child} = Jv_{parent} \Rightarrow f_{parent} += J^T f_{child}$
- Conservation of momentum :
  Mass is modeled at one level only. There is no transfer of momentum.
- Constraints on displacements (e.g. incompressibility, fixed points) are not easily applied *at the child level*

Outline

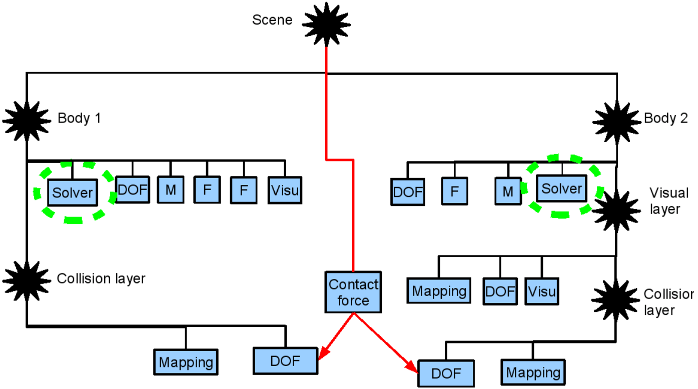
Two bodies in contact

Use extended trees (Directed Acyclic Graphs) to model trees with loops.



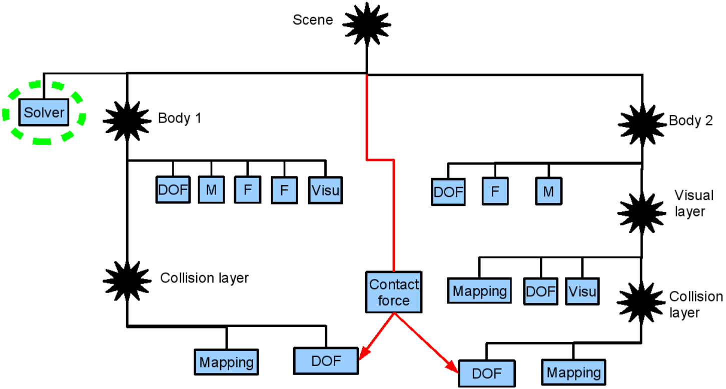


ODE solution of interacting bodies



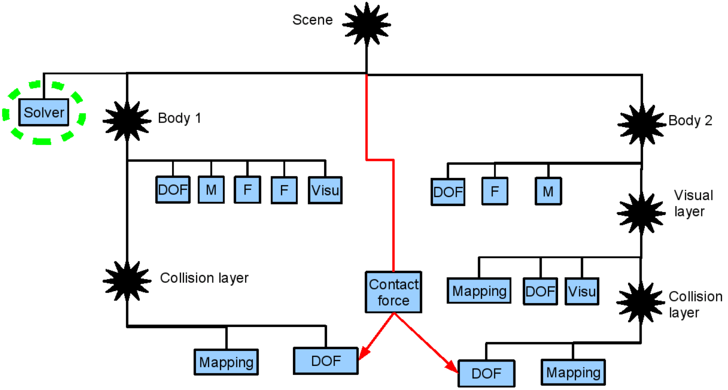
- Soft interactions : independent processing, no synchronization required

ODE solution of interacting bodies



- Soft interactions : independent processing, no synchronization required
- Stiff interactions : unified implicit solution, synchronized objects

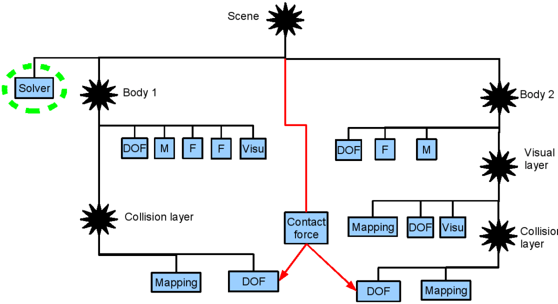
ODE solution of interacting bodies



- Soft interactions : independent processing, no synchronization required
- Stiff interactions : unified implicit solution, synchronized objects
- Hard interaction constraints : work in progress *(Christian Duriez, ALCOVE)*

Outline

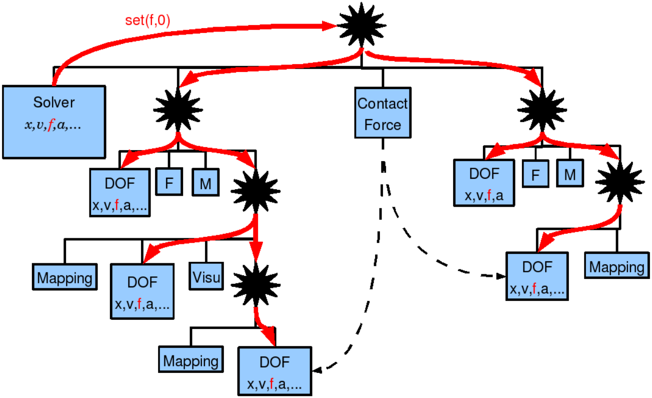
Actions



- No global state vector
- Action = graph traversal + global vector ids + call of abstract top-down and bottom up methods

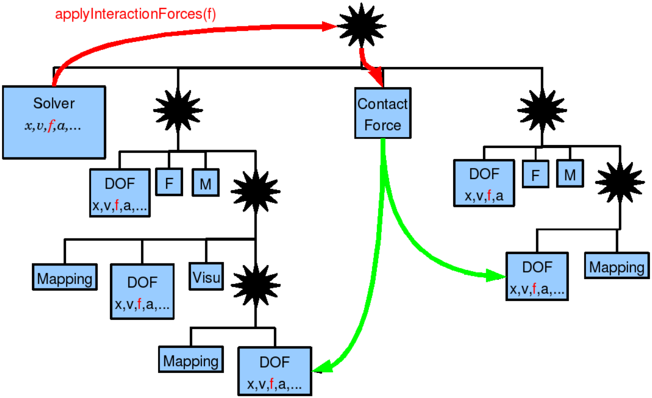
Example : clearing a global vector

- The solver triggers an action starting from its parent system and carrying the necessary symbolic information
- the action is propagated through the graph and calls the appropriate methods at each DOF node



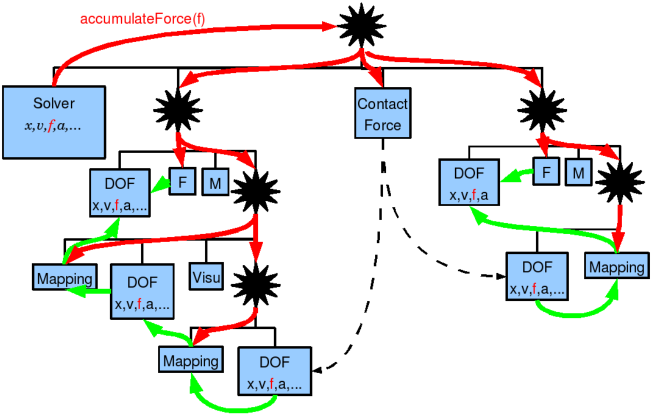
Example : applying interaction forces

- The solver triggers the appropriate action
- the action is propagated through the graph and calls the appropriate methods at each Contact node



Example : accumulating the forces

- The solver triggers the appropriate action
- the action is propagated through the graph and calls the appropriate (botom-up) methods at each Force and Mapping node



Efficient implicit integration

- Large time steps for stiff internal forces and interactions
- solve $(\alpha M + \beta h^2 K)\Delta v = h(f + hKv)$ Iteratively using a cojugate gradient solution

Actions :

- propagateDx
- computeDf
- vector operations
- dot product (only global value directly accessed by the solver)

Ongoing work : building global vectors and matrices also

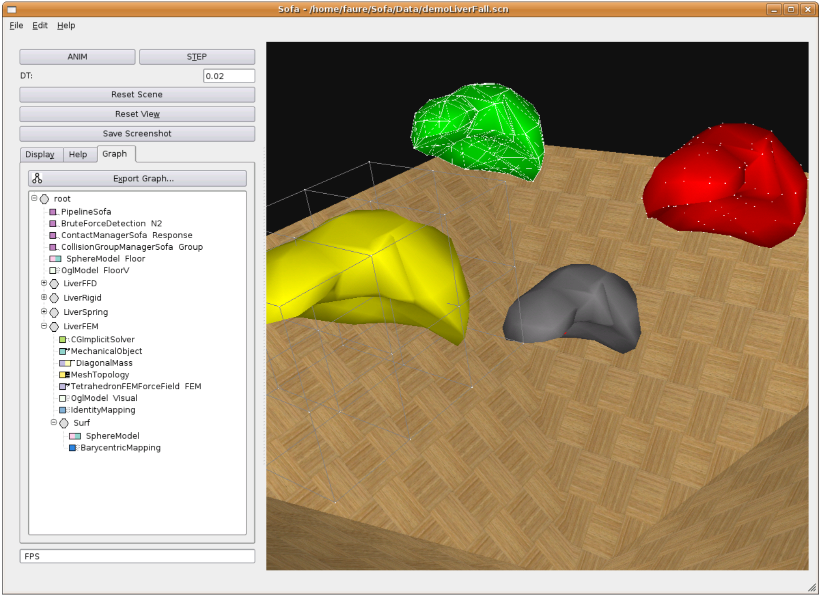
Efficiency

- No global state vector
  - they are scattered over the DOF components
  - each DOF component can be based on its own types (e.g. Vec3, Frame, etc.)
  - symbolic values are used to represent global state vectors
- Action = graph traversal + global vector ids + call of abstract top-down and bottom up methods
  - Displacements are propagated top-down
  - Interactions forces are evaluated after displacement propagation
  - Forces are accumulated bottom-up
  - Branches can be processed in parallel
  - virtual functions applied to components

Outline

Current stage

About 60 man.month, 20000 C++ code lines



Efficient coupling

High modularity :

- Abstract components : DOF, Force, Constraint, Solver, Topology, Mass, CollisionModel, VisualModel, etc.
- Arbitrary DOF types can coexist in the same scene

Efficiency :

- global vectors and matrices are avoided
- parallel processing is allowed

Implementation :

- currently 20000 C++ lines
- Windows, Linux
- Qt or FLTK user interfaces
- XML file format

Ongoing work

- More people : ETHZ, ...
- More algorithms : cutting *(Hervé Delingette, ASCLEPIOS)*, interfaces *(François Faure, EVASION)*,...
- More schedulers : asynchronous simulation/rendering/haptic feedback *(Jeremie Allard, Cimit)*
- More brute force : parallelization on PC cluster *(Everton Hermann, LIG/LJK)*
- More visual performance : coupling to a good render engine *(Pierre-Jean Bensoussan, ALCOVE)*
- More documentation *(everybody...)*
- Licensing

www.sofa-framework.org