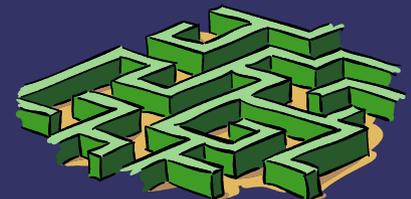


***Spatial Data Management
for
Virtual Product Development***

Andreas Lavén & Rikard Boström

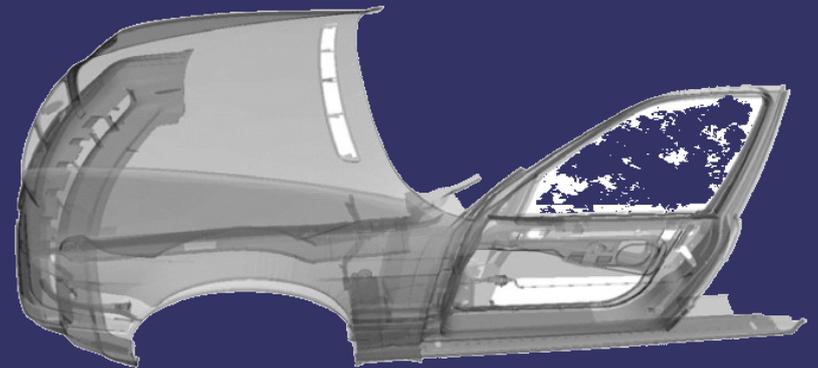


CAD

⇒ Computer Aided Design

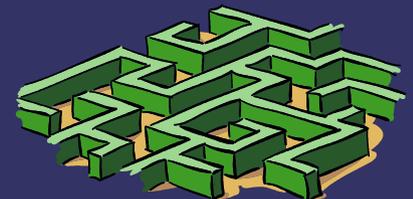
⇒ Used for

- Cars
- Buildings
- etc.



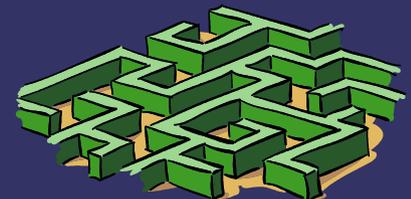
Intro

- ➔ New possibilities with CAD files
- ➔ New requirements of databases
- ➔ Solutions



Spatial engineering

- ➔ Mechanical engineering
- ➔ Possible to test models without physical product
- ➔ New requirements for databases



Engineering Data Management

- ➔ Old system of databases
- ➔ Hierarchal
- ➔ DIVE



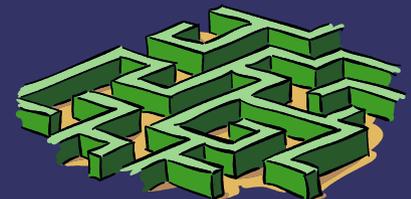
Digital Mock-Up

- ⇒ Often late changes
- ⇒ DMU enables fast detection of collisions
- ⇒ Main memory
 - well-assembled list
 - few parts
- ⇒ Earlier manually selection of parts



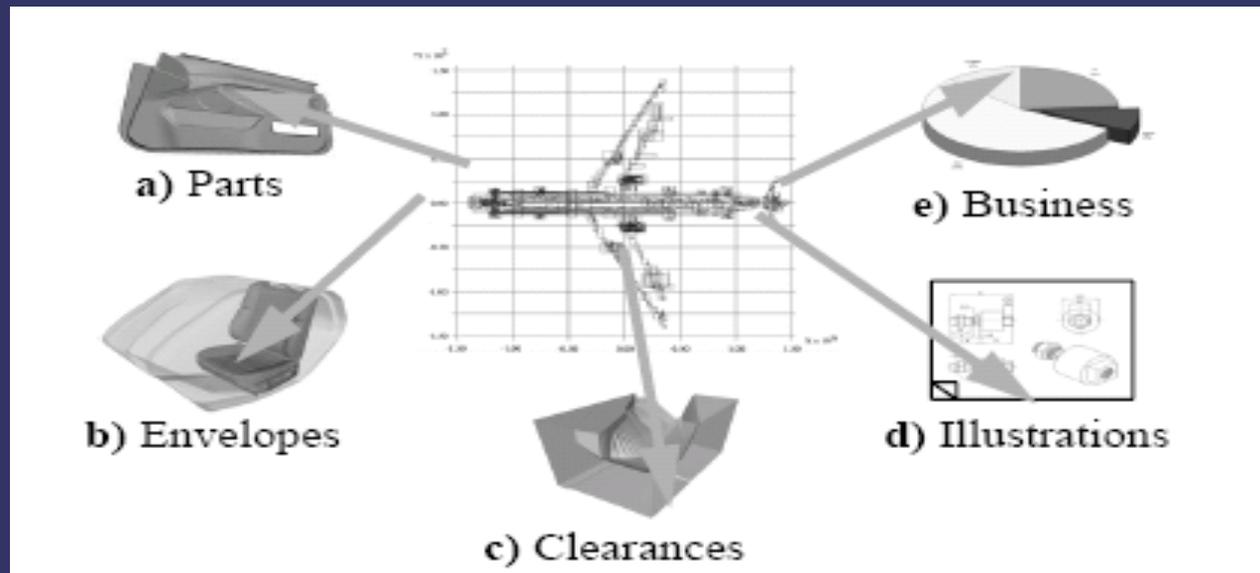
Haptic rendering

- ➔ Emulate forces towards CAD objects
 - To prevent parts from colliding
- ➔ Fast database is important



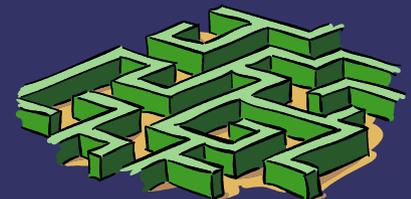
Spatial document management

- ➔ Files besides CAD files will be changed
- ➔ References to data
 - free space around hot parts
 - number of passenger
 - costs



Operations on Spatial Engineering data

- ➔ Product = Collection of 3d-parts
- ➔ 3d-part = High precision complex geometric shape
- ➔ Geometric data models for representation:
 - Triangle meshes (Visualization, interference detection)
 - Voxels (Spatial keys)
 - Point Shells (RealTime Haptic Rendering)



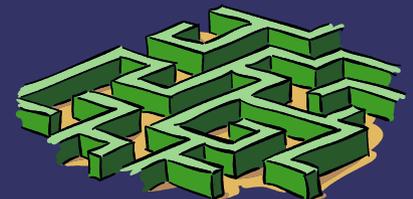
Triangle Meshes

- ➔ Accurate representations of original surfaces often implemented by bicubic surfaces
 - Too complex for efficient spatial computations
- ➔ Triangle mesh (Polygons) can be derived from original representations
 - Allows efficient spatial computing



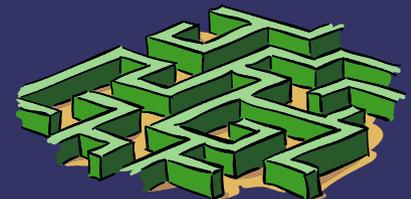
Collisions Queries

- ➔ Important database primitive
- ➔ Three different actions:
 - Collision detection
 - Collision determination
 - Collision response



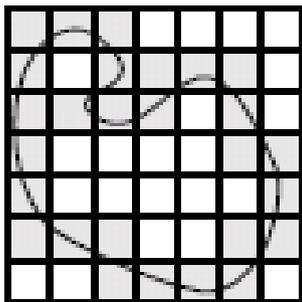
Voxels

- ➔ “3D-pixels”, atomic unit (cube) in 3D-space
- ➔ Algorithm for transferring triangle meshes to voxelobjects
 - Runs in $O(N)$, N = number of voxels
 - Produces an approximation of the surface

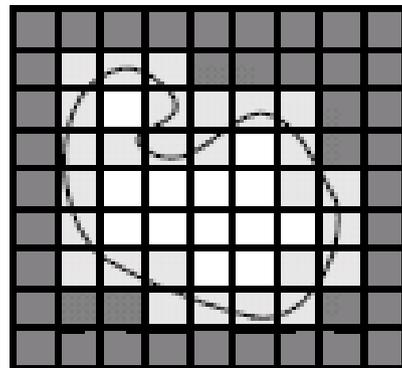


Problems in conversion

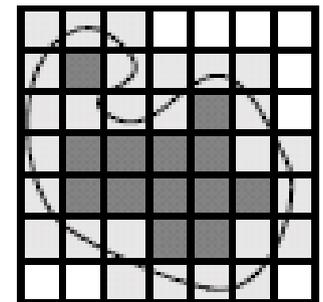
- ➔ Triangle meshes often contain geometric and topological inconsistencies (gaps, overlaps)
 - Robust reconstruction of original interior becomes very laborious



a) Voxelized surface



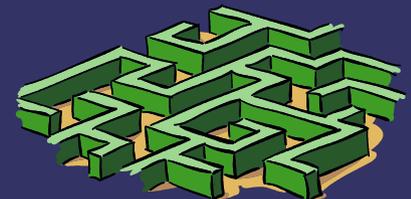
b) Filled exterior



c) Inverted result

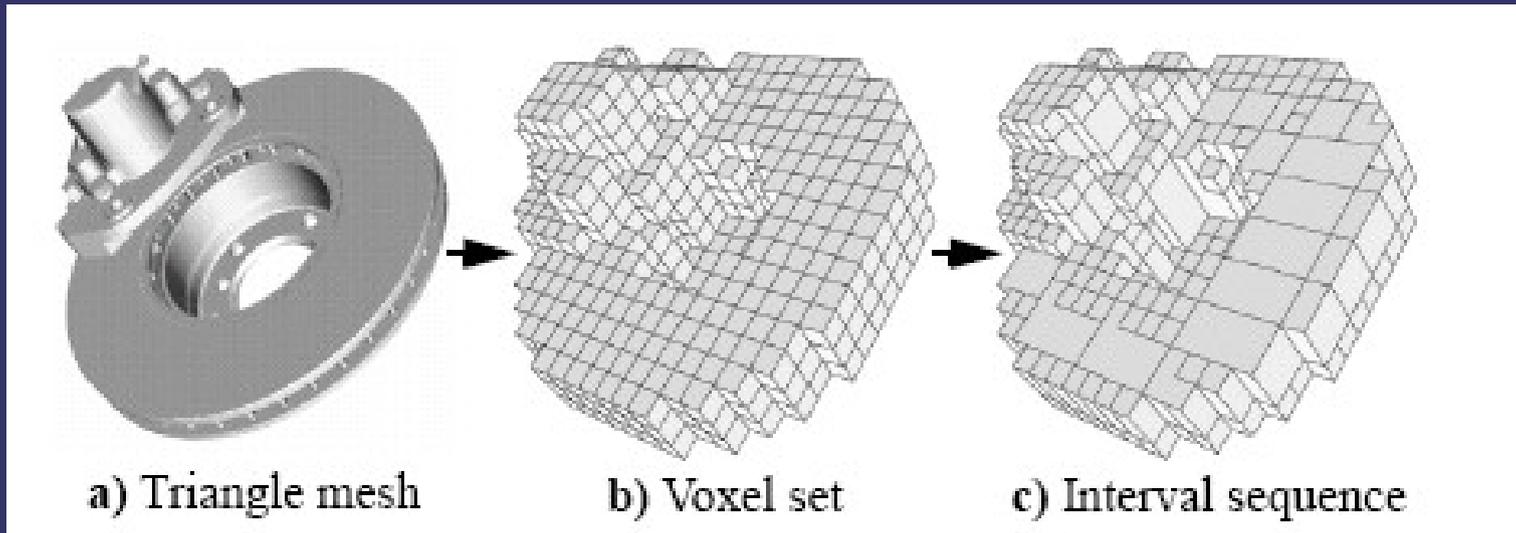
Interval sequences

- ➔ Grid covering complete data space
- ➔ Voxel corresponds to one cell
- ➔ Each cell encoded by single integer
- ➔ Object = set of integers
 - Adjacent cells presented by contiguous integers, an interval

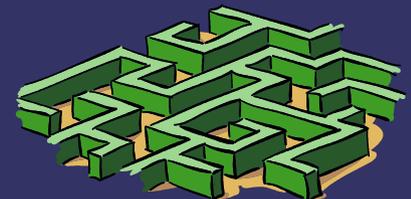


Pipeline process

- ➔ Triangle mesh -> Voxel set – Intervals



- ➔ Hilbert Algorithm



Point Shells

- ➔ Realtime interference detection requirements:
 - Efficient geometric transformation (1)
 - Efficient intersection tests (2)
- ➔ Triangle meshes fails (2)
- ➔ Voxel fails (1)
- ➔ Point shells solves the problem



Creation of Point Shells

- ➔ Triangle mesh
- ➔ Voxelize
- ➔ Centerpoints of boundary voxels
- ➔ Interpolate closest surface point to voxel-center
- ➔ Compute normal vector for each point, pointing inwards

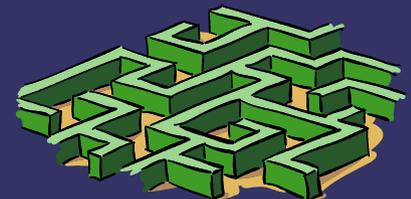
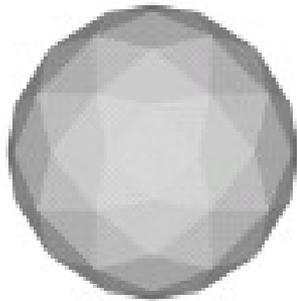
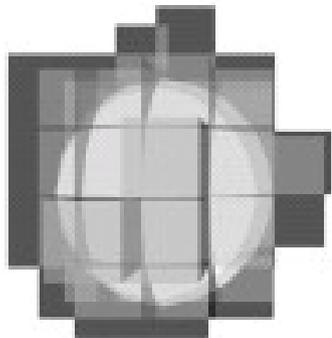


Illustration and use

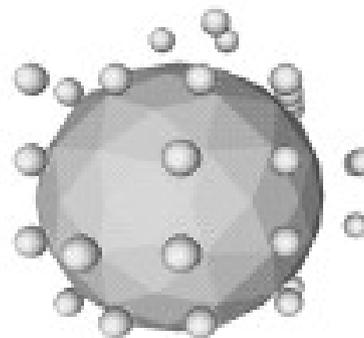
- ⇒ Voxels used for static environment
- ⇒ Point Shell used for moving object



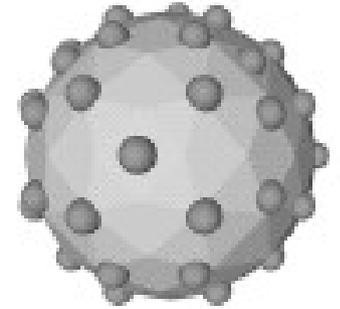
a) Triangulation



b) Voxelization



c) Center points



d) Surface points

Relational Interval Tree

- ➔ Storing and indexing intervals
- ➔ Virtual binary tree
- ➔ One tree for each axis in space (?)
- ➔ Possible to find intersections in $\log(N)$



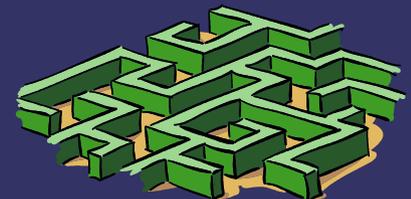
DIVE

- ➔ Database integration of Virtual Engineering
- ➔ Architecture for integrating mentioned techniques into existing EDM-systems
- ➔ Spatial data management – use a region of space as a key
 - Reference documents, CAD-files spatially
- ➔ Main problems:
 - Store spatial data in conventional databases
 - Efficient geometric queries



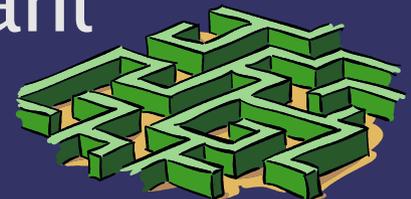
Solution

- ➔ Use conversion pipeline for objects -> intervals and store in RI-trees
- ➔ Spatial part of queries works on RI-trees
- ➔ Non-spatial part works on EDM
- ➔ Current version supports 3 spatial queries:
 - Volume query
 - Collision query
 - Clearance query

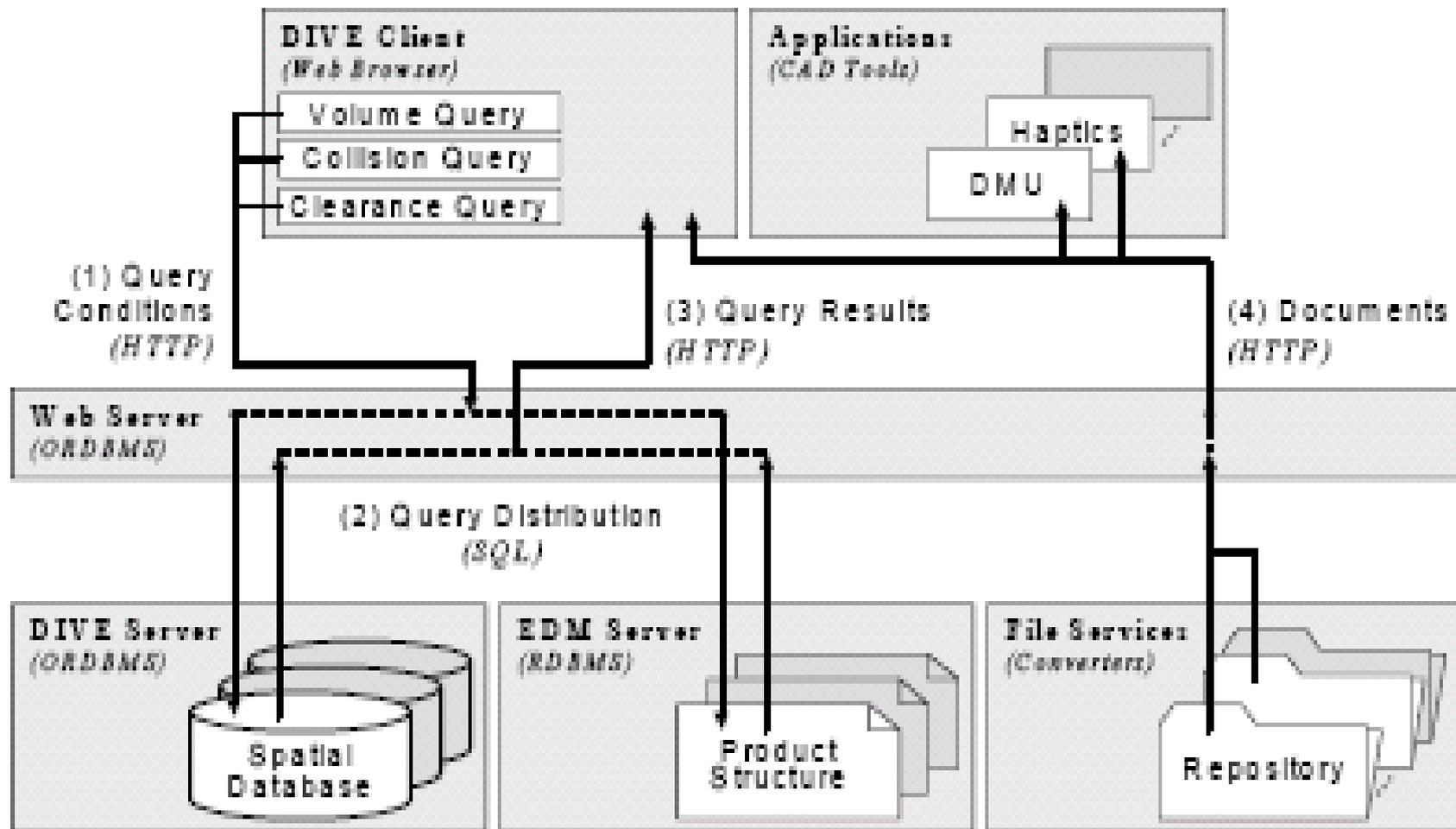


Refined DMU

- ➔ Used for demonstrating capabilities of DIVE
- ➔ Results from spatial queries can be used in next query
 - Enables user to spatial browse large databases with interactive response times
- ➔ Supports ranking of query results according to e.g. intersect volume
 - Can be used to detect most relevant problems



System Architecture



Industrial Evaluation

- ➔ Athlon 750
- ➔ IDE Harddrives
- ➔ 11,200 Spatial keys
- ➔ Volume / Collision queries averaged 0,7s
- ➔ Logarithmic scale up make interactive responses times possible for much larger databases

