

# **SAND REPORT**

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## **ACME Algorithms for Contact in a Multiphysics Environment API Version 1.3**

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**API Version 1.3**

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**Abstract**

An effort is underway at Sandia National Laboratories to develop a library of algorithms to search for potential interactions between surfaces represented by analytic and discretized topological entities. This effort is also developing algorithms to determine forces due to these interactions for transient dynamics applications. This document describes the Application Programming Interface (API) for the ACME (Algorithms for Contact in a Multiphysics Environment) library.



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## 1. Introduction

Contact algorithms play an important role in many research and production codes that simulate various interfacial aspects of continuum solid and fluid mechanics and energy transport. Because of the difficult nature of contact in general and in order to concentrate and leverage development efforts, an effort is underway at Sandia National Laboratories to develop a library of algorithms to search for potential interactions between surfaces represented by finite element meshes and other topological entities. The requirements for such a library, along with other pertinent information, are documented at the following World Wide Web site:

<http://www.jal.sandia.gov/SEACAS/AcmeWeb/html/index.html>

This document describes the Application Programming Interface (API) for the ACME search and transient dynamics enforcement library. (In an attempt to avoid confusion, capitalized terms are used in this document to refer to specific terminology for which detailed definitions are provided. A glossary of these terms is given in Appendix A.) This introductory section gives an overview of the concepts and design of the ACME interface and outlines the building blocks that make up the data ACME needs from the host code and the data it returns to the host code. Section 2 describes various utility functions used to extract information about the package and its operation. Section 3 describes functions needed to access and utilize the search capabilities of ACME. Section 4 describes functions that can remove an initial overlap for a mesh prior to beginning a transient. Section 5 describes functions which ACME provides to enforce the results of the search in explicit transient dynamics simulations. Section 6 describes functions for a tied kinematic enforcement capability that allows nodes to be tied to faces and satisfy a no-relative-motion requirement. Section 7 describes functions that perform volume-weighted node and element variable transfers based on the element volume overlap returned by the search object. Section 8 describes functions which ACME provides to build multiple point constraint (MPC) equations which the host code may use to enforce node-face interactions returned by the search. Finally, Section 9 provides an example of how to use the API within a C++ application.

The basic philosophy of the ACME interface is to provide a separate function to support each activity. Efforts have been made to have the C++, C, and Fortran interfaces appear as similar as possible. It is important to note that all array indexes use the Fortran convention (i.e., indexes start with 1) and all floating-point data are double precision.

This release of the ACME library contains only a subset of the algorithms and functionality required to meet all the needs of the application codes. Currently, ACME supports three-dimensional (3D) topologies in serial and in parallel processing modes. No multi-state support is provided in this release (i.e., ACME has no ability to revert to previous states). ACME only supports conventional nodes (smooth particle hydrodynamics nodes are not yet supported) and a limited set of face types (a linear 4-node quadrilateral, a quadratic 8-node quadrilateral, a linear 3-node triangle, and a quadratic 6-node triangle) in this release. This release provides a preliminary implementation of shell contact which in-

volves the lofting of shell surfaces. Shell contact in this version of ACME is subject to the following restrictions: at most two shells can share a single edge, shells can not be involved with element birth/death or dynamic load balancing, and restarts with shells is only supported through the variable restart interface. This release also only supports element-element searches using 8-node hex elements, and at least one of the elements in the search be a Cartesian hex. Additional algorithms and functionality will be added in subsequent releases.

### 1.1 Topology

The topology for ACME is determined by the host code. The first step in using the library is for the host code to provide to ACME a topological description of the surfaces to be checked for interactions, or the elements to be checked for overlap. Currently, the topology consists of collections of nodes, faces, elements, and analytic surfaces. Nodes, faces, and elements are supplied to ACME in groups called blocks. A `Node_Block` may contain only one type of node. A `Face_Block` may contain only one type of face and all faces will have the same `Entity_Key`. (`Entity_Keys` are used to extract user-specified parameters from the `Search_Data` array for pairs of interacting topological entities, as explained in Section 1.1.5). An `Element_Block` may contain only one type of element, and all elements will have the same `Entity_Key`. Currently, a single search object should not contain both `Face_Blocks` and `Element_Blocks`. Providing the full functionality required of ACME will necessitate adding `Edge_Blocks`, which will be analogous to `Face_Blocks` (see the description in Section 1.1.2). Also, the full functionality required of ACME will necessitate adding multiple states; for this initial release of ACME, only a single state (with one or two configurations) is supported.

#### 1.1.1 Node\_Blocks

A `Node_Block` is a collection of nodes of the same type. Currently, the only type of node supported in ACME is a conventional node that has a position attribute and an optional projection direction attribute (for face/face search; see Section 1.3.3). Eventually three types of nodes will be supported:

**NODE:** A traditional node with position and an optional projection direction attribute.

**NODE\_WITH\_SLOPE:** A higher-order shell node that has a first derivative as an attribute and an optional projection direction attribute.

**NODE\_WITH\_RADIUS:** A node that has a radius as an attribute and an optional projection direction attribute. This radius is associated with the size of a spherical domain, as with smooth particle hydrodynamics (SPH) particles.

In this release only `NODE` `Node_Blocks` are supported. All of the nodes that are connected to faces must be in the first `Node_Block`. Other `Node_Blocks` can be used for nodes not connected to faces in the `ContactSearch` topology. These additional `Node_Blocks` can be used for SPH particles (neglecting the radius of the particle) or for finding the Gauss point locations on the other side of an interface. Since all nodes connected to faces must be in `Node_Block 1`, the nodal communication lists refer only to nodes in `Node_Block 1`.

Each `Node_Block` is assigned an integer identifier (ID). This ID corresponds to the order in which the blocks were specified, using the Fortran numbering convention (i.e., the first block has an ID of 1, the second block has an ID of 2, etc.). This ID is used in specifying configurations for `Node_Blocks`, and for returning `NodeFace_Interactions` and `NodeSurface_Interactions`, discussed later in Section 1.3.

### 1.1.2 Face\_Blocks

A `Face_Block` is a collection of faces of the same type that have the same `Entity_Key`. (`Entity_Keys` are used to extract user-specified parameters from the `Search_Data` array, as explained in Section 1.1.5.) Currently, ACME supports a linear 4-node quadrilateral face called `QUADFACEL4`, a quadratic 8-node quadrilateral face called `QUADFACEQ8`, a linear 3-node triangular face called `TRIFACEL3`, and a quadratic 6-node triangular face called `TRIFACEQ6`. It also supports shell versions of the linear 4-node quadrilateral and 3-node triangular faces, called `SHELLQUADFACEL4` and `SHELLTRIFACEL3`, respectively. Other face types will be added as needed. These are provided in an enumeration in the `ContactSearch` header file:

```
enum ContactFace_Type {
    QUADFACEL4 = 1,
    QUADFACEQ8,
    TRIFACEL3,
    TRIFACEQ6,
    SHELLQUADFACEL4,
    SHELLTRIFACEL3
}
```

Each `Face_Block` is assigned an ID. This ID corresponds to the order in which the blocks were specified. This ID is used in returning `NodeFace_Interactions`.

Specifying shell versions of the faces (`SHELLQUADFACEL4` and `SHELLTRIFACEL3`) indicate to the ACME library that a lofted geometry is to be created for the faces in the corresponding blocks. Both the top and bottom faces of each shell must be included in the face blocks passed to ACME, though the two faces are not required to be in the same block. Note that ACME currently requires that shells share their edges with at most one other shell.

ACME does not currently support the mixing of face blocks and element blocks in a single search object.

### 1.1.3 Element\_Blocks

An `Element_Block` is a collection of elements of the same type that have the same `Entity_Key`. (`Entity_Keys` are used to extract user-specified parameters from the `Search_Data` array, as explained in Section 1.1.5.) Currently, two forms of an eight-node hex are supported: `CARTESIANHEXELEMENTL8`, which has each face aligned with a Cartesian plane, and `HEXELEMENTL8`, which is an arbitrary eight-node hex. Other ele-

## Introduction

ment types will be added as needed. These are provided in an enumeration in the Contact-Search header file:

```
enum ContactElement_Type {  
    CARTESIANHEXELEMENTL8 = 1,  
    HEXELEMENTL8 }  
}
```

Each `Element_Block` is assigned an ID. This ID corresponds to the order in which the blocks were specified, using the Fortran numbering convention. This ID is used in returning `ElementElement_Interactions`.

ACME does not currently support the mixing of face blocks and element blocks in a single search object. Also, ACME currently requires that at least one of the element blocks involved with every element-element search be a Cartesian hex. Element-element searches between two `HEXELEMENTL8` `Element_Blocks` is not permitted.

### 1.1.4 Analytic\_Surfaces

In many instances, it is advantageous to search for interactions against rigid analytic surfaces (referred to as `Analytic_Surfaces` throughout this document) rather than mesh such a surface. Examples include a tire rolling on a flat road or dropping a shipping container on a post. Currently, ACME is designed to handle only geometric `Analytic_Surfaces` (e.g., planes, cylinders, etc.), and for now, only planar, spherical and cylindrical `Analytic_Surfaces` are supported. Other geometric `Analytic_Surfaces` will be added in the future as needed. Eventually, `Analytic_Surfaces` defined by Non-Uniform Rational B-Splines (NURBS) will be supported. The ACME API will need to be extended to support `Analytic_Surfaces` defined by NURBS. `Analytic_Surfaces` currently can interact only with nodes, not faces or elements. `Analytic_Surfaces` should not be specified for search objects that only contain elements.

`Analytic_Surfaces`, if any, are provided by the host code to ACME after the `Node_Blocks` and `Face_Blocks` have been specified. `Analytic_Surfaces` are given an ID that corresponds to the total number of `Face_Blocks` plus the order in which the `Analytic_Surface` was added (e.g., if three `Face_Blocks` exist in the topology, the ID of the first `Analytic_Surface` is 4, the ID of the second `Analytic_Surface` is 5, etc.). This ID is used in returning `NodeSurface_Interactions`.

### 1.1.5 Search\_Data

The `Search_Data` array contains data that describe how the various topological entities are allowed to interact. The host code may specify, for example, that only nodes on surface A interact with faces on surface B, or that only nodes on surface B interact with faces on surface A, or both. The `Search_Data` array is the only place where such user-specified data are kept.

Currently the `Search_Data` array holds only three parameters for each `Entity_Key` pair. The first parameter is a status flag indicating what type of interactions should be defined

for this pair. Eight values are currently permitted, provided in an enumeration in the ContactSearch header file:

```
enum Search_Interaction_Type{
    NO_INTERACTION = 0,
    SLIDING_INTERACTION,
    TIED_INTERACTION,
    FACE_FACE_INTERACTION,
    FACE_COVERAGE_INTERACTION,
    NFI_AND_FFI,
    NFI_AND_FCI,
    ELEMENT_ELEMENT_INTERACTION};
```

NO\_INTERACTION (a value of 0) requests that no interactions be defined for this pair of entities. SLIDING\_INTERACTION (a value of 1) requests that ACME search for new node/face or node/surface interactions between entities each time a search is executed. TIED\_INTERACTION (a value of 2) requests that a node/face or node/surface interaction between entities persist over multiple time steps, thus allowing it to be used for mesh tying. FACE\_FACE\_INTERACTION (a value of 3) requests that ACME search for new face/face interactions between entities each time a search is executed. FACE\_COVERAGE\_INTERACTION (a value of 4) requests that ACME search for new face/coverage interactions between entities each time a search is executed. In addition, it requires that a face/face search also be performed. NFI\_AND\_FFI (a value of 5) requests that ACME search for new node/face or node/surface interactions and face/face interactions between entities each time a search is executed. NFI\_AND\_FCI (a value of 6) requests that ACME search for new node/face or node/surface interactions and face/coverage interactions between entities each time a search is executed. In addition, it requires that a face/face search also be performed. ELEMENT\_ELEMENT\_INTERACTION (a value of 7) requests that ACME search for overlap between the elements of the two element blocks.

The second parameter in the Search\_Data array is the Search\_Normal\_Tolerance, which is used to determine whether the entity pair should interact, based on the separation between the entities (see Figure 1). Note that the Search\_Normal\_Tolerance is an absolute distance, so it is dependent on the units of the problem. The third parameter is the Search\_Tangential\_Tolerance, also used to determine whether the entity pair should interact, but taking into account distances tangential to a face, rather than normal to it. Element-Element interactions do not use either tolerance, so they should be set to zero.

Every face, element, and node is assigned an Entity\_Key to allow retrieval of data from the Search\_Data array. For faces, the Entity\_Key corresponds to the Face\_Block ID. For elements, the Entity\_Key corresponds to the Element\_Block ID. Currently, a node inherits its Entity\_Key from the first face that contains it. This is a limitation of the current implementation, since a node can be connected to two or more faces that are in different Face\_Blocks.

The Search\_Data array is a three-dimensional Fortran array with the following size

## Introduction

```
dimension search_data(3,num_entity_keys,num_entity_keys)
```

The first index represents one of the three parameters described previously for each entity pair, currently a node-face, node-Analytic\_Surface, face-face, or element-element pair. The second index indicates the Entity\_Key for the node, face, or element in an interaction, and the third index indicates the Entity\_Key for the face, element, or Analytic\_Surface in an interaction.

### 1.2 Search Algorithms

ACME provides four different algorithms for determining interactions. The data types returned in the interactions are the same for each type of search. The host code may use different types of search algorithms during an analysis (e.g., a static 1-configuration search to determine overlaps in the mesh before starting the analysis and then a dynamic search once time stepping begins in a transient dynamics code).

As an aid to understanding the differences between the search algorithms, consider the idealized 2D face of Figure 1. In this idealized example, the subtleties of what happens at the edge of a face are ignored. Any entity that is outside the face, where “outside” is defined by the outward unit normal  $\mathbf{n}$ , is not penetrating and has a positive Gap. Any entity that is on the face (i.e., a zero Gap) or inside the face (i.e., a negative Gap) is considered to be penetrating. The host code controls the Search\_Normal\_Tolerance as part of the Search\_Data array (see Section 1.1.5). The Motion\_Tolerance accounts for movement of the node if two configurations are used, and is computed by ACME.

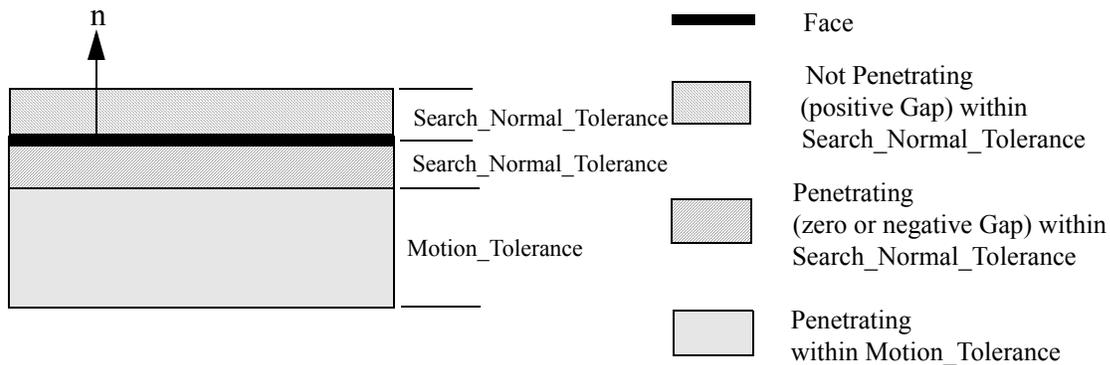


Figure 1 Idealized 2D face with Search\_Normal\_Tolerance

A separate tolerance, Search\_Tangential\_Tolerance, is used to specify the behavior of the search algorithms along the edge of a face. As shown in Figure 2, a NodeFace\_Interaction will be defined for any node that is outside the face tangentially but within the Search\_Tangential\_Tolerance. The host code controls the Search\_Tangential\_Tolerance as part of the Search\_Data array (see Section 1.1.4).

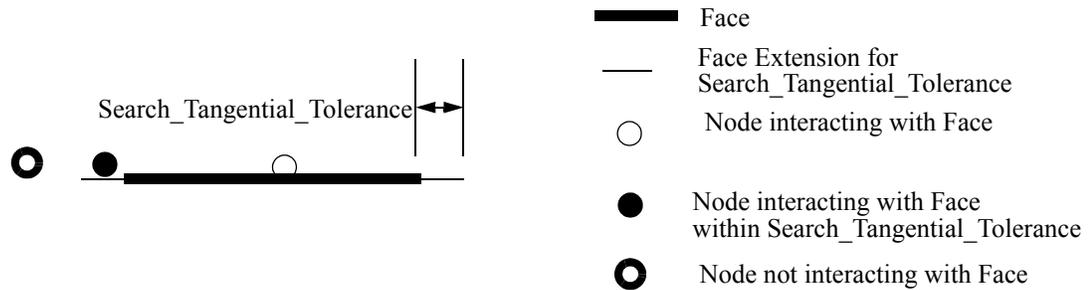


Figure 2 Idealized 2D face with Search\_Tangential\_Tolerance

### 1.2.1 Static 1-Configuration Search Algorithm

The static 1-configuration search algorithm uses only one configuration for the topology. The interactions are determined using only a closest point projection algorithm. Interactions are defined only for entities that are within the Search\_Normal\_Tolerance (either negative or positive Gap) and the Search\_Tangential\_Tolerance. The Motion\_Tolerance is implied to be zero. This search must be used for face-face and element-element interactions.

### 1.2.2 Static 2-Configuration Search Algorithm

The static 2-configuration search algorithm requires two configurations (Current and Predicted) for the topology. This search algorithm uses closest point projection on the predicted configuration but it has the added information of the movement of the topology. The motion tolerance implied by the two configurations is used along with the Search\_Data to determine what interactions are physically realistic. Specifically, any node that has a positive Gap within the Search\_Normal\_Tolerance or any node that has a negative Gap within the Search\_Normal\_Tolerance plus the motion tolerance will result in an interaction being defined, provided that the node's projection falls within the face boundary as extended laterally by the Search\_Tangential\_Tolerance. This search is not supported for face-face or element-element searches; only the static 1-configuration search will operate for these cases.

### 1.2.3 Dynamic 2-Configuration Search Algorithm

The dynamic 2-configuration search algorithm also requires two configurations (Current and Predicted) for the topology. A dynamic intersection algorithm based on linear interpolation of the motion is used to initiate interaction if the current and predicted Gaps are on opposing sides of the face (e.g., the current configuration has a positive Gap and the predicted configuration has a negative Gap). A closest point projection algorithm is used for subsequent interaction definition and to initiate interaction if the current and predicted Gaps are on the same side of the face. In these cases, interactions are defined by the same

criteria as in the static 2-configuration search algorithm (see Figure 1). This search is not supported for face-face or element-element searches; only the static 1-configuration search will operate for these cases.

### 1.2.4 Dynamic Augmented 2-Configuration Search Algorithm

The dynamic augmented 2-configuration search algorithm is a more accurate implementation of the dynamic 2-configuration search algorithm. This search can only be used in conjunction with the ContactTDEnforcement enforcement algorithm. It uses information from the enforcement on the previous step to compute an augmented configuration that yields more accurate interactions. This search is not supported for face-face or element-element searches; only the static 1-configuration search will operate for these cases.

## 1.3 Interactions

The output of ACME following a search is a collection of interactions based on the topology, configuration(s), Search\_Data, and search algorithm. Currently, five types of interactions are supported: NodeFace\_Interactions, NodeSurface\_Interactions, FaceFace\_Interactions, FaceCoverage\_Interactions, and ElementElement\_Interactions. ACME does not determine the *best* interaction between these types (i.e., ACME does not compete a NodeFace\_Interaction against a NodeSurface\_Interaction when the same node is involved; both are returned to the host code). Other interaction types (e.g., EdgeFace\_Interaction) will be added in the future. The FaceFace\_Interactions, FaceCoverage\_Interactions, and ElementElement\_Interactions are only available in the static 1-configuration search.

### 1.3.1 NodeFace\_Interactions

A NodeFace\_Interaction is returned as a set of data to the host code: a node (indicated by the Node\_Block ID and the index in that Node\_Block), a face (indicated by the Face\_Block ID and the index in that Face\_Block) and data describing the interaction. Consider the examples shown in Figure 3. The first diagram illustrates an interaction defined using the dynamic intersection algorithm. Here, a node, lightly shaded in its current configuration and black in its predicted configuration, intersects a TRIFACEL3 at **X** in an intermediate configuration denoted with white nodes. The motion of the node is represented by the vector  $v_s$ . Also shown are the data that are returned for this interaction. Specifically, the pushback direction is given by the vector from the penetrating node's predicted position to the position of the contact point convected into the predicted configuration. In the second diagram, the contact point **X**, determined by closest point projection for a single configuration, is shown in local coordinate space for a QUADFACEL4. Table 1 gives the Fortran layout of how the data are returned. It should be noted that only two local coordinates are returned. For triangular faces, the third local coordinate is simply unity minus the sum of the other two local coordinates.

Currently, ACME can not return NodeFace\_Interactions for shell faces (SHELLQUADFACEL4 and SHELLTRIFACEL3).

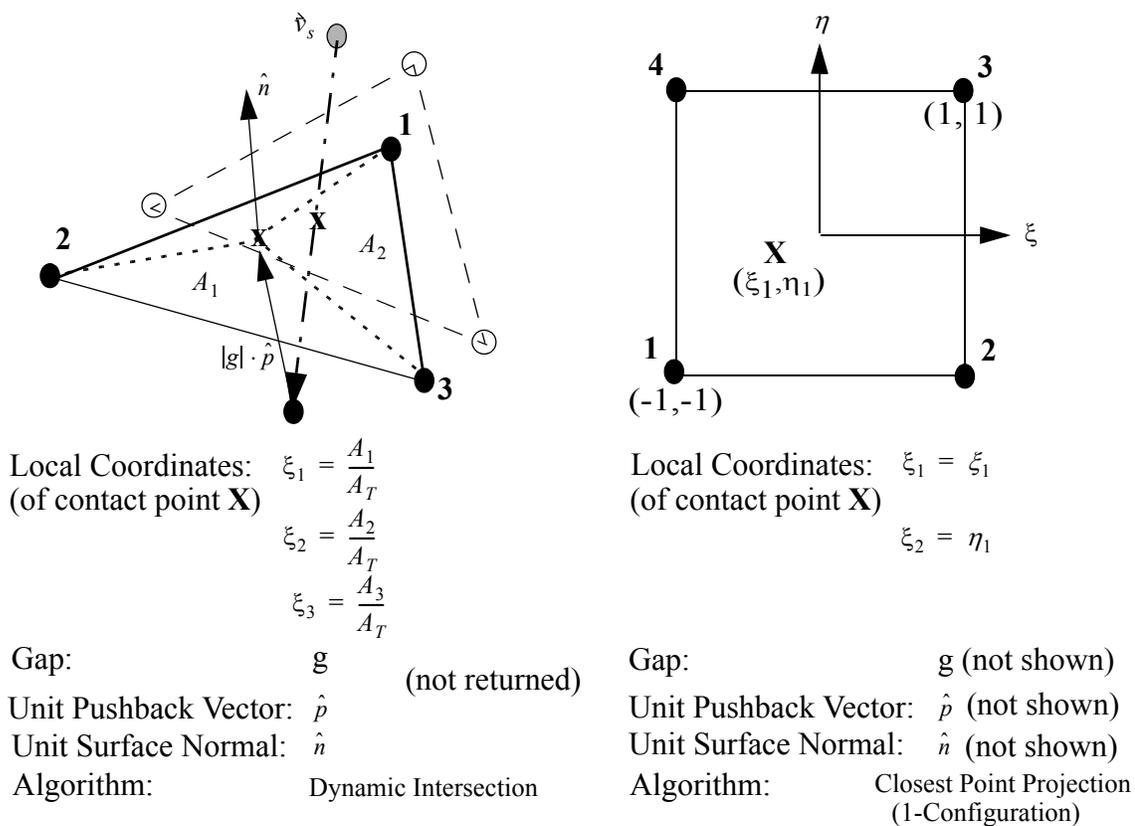


Figure 3 3D NodeFace\_Interactions

Table 1 NodeFace\_Interaction Data for 3D

Location (Fortran Indexing)	Quantity
1	Local Coordinate 1 ( $\xi_1$ for Q4 or Q8, $\xi_1$ for T3 or T6)
2	Local Coordinate 2 ( $\eta_1$ for Q4 or Q8, $\xi_2$ for T3 or T6)
3	Gap
4-6	Unit Pushback Vector (x, y & z components)
7-9	Unit Surface Normal (x, y & z components)
10	Algorithm Used to Define Interaction {1=Closest Point Projection (1 Configuration), 2=Closest Point Projection (2 Configuration), 3=Dynamic Intersection (2 Configuration)}

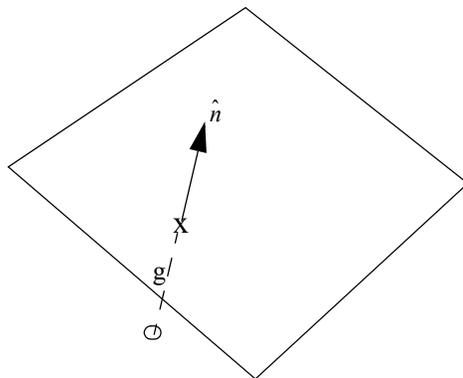
### 1.3.2 NodeSurface\_Interactions

A NodeSurface\_Interaction is returned as a set of data to the host code: a node (indicated by the Node\_Block ID and the index in that Node\_Block), an Analytic\_Surface (indicated by its ID) and the data describing the interaction. Figure 4 shows the interaction data that are returned to the host code for each interaction. Table 2 gives the layout of the data for a NodeSurface\_Interaction.

For this release of ACME, NodeSurface\_Interactions are determined using a closest point projection algorithm. Therefore, only one configuration is required for the Analytic\_Surfaces. The configuration used for the nodes is based on the current configuration for a 1-configuration static search and the predicted configuration for the 2-configuration static search or the dynamic searches. This limitation will be removed in a future release.

Table 2 NodeSurface\_Interaction Data for 3D

Location (Fortran Indexing)	Quantity
1-3	Interaction Point (x, y & z coordinates)
4	Gap
5-7	Unit Surface Normal (x, y & z components)



Interaction Point:  $x$   
 Gap:  $g$   
 Unit Surface Normal:  $\hat{n}$

Figure 4 3D NodeSurface\_Interaction Data

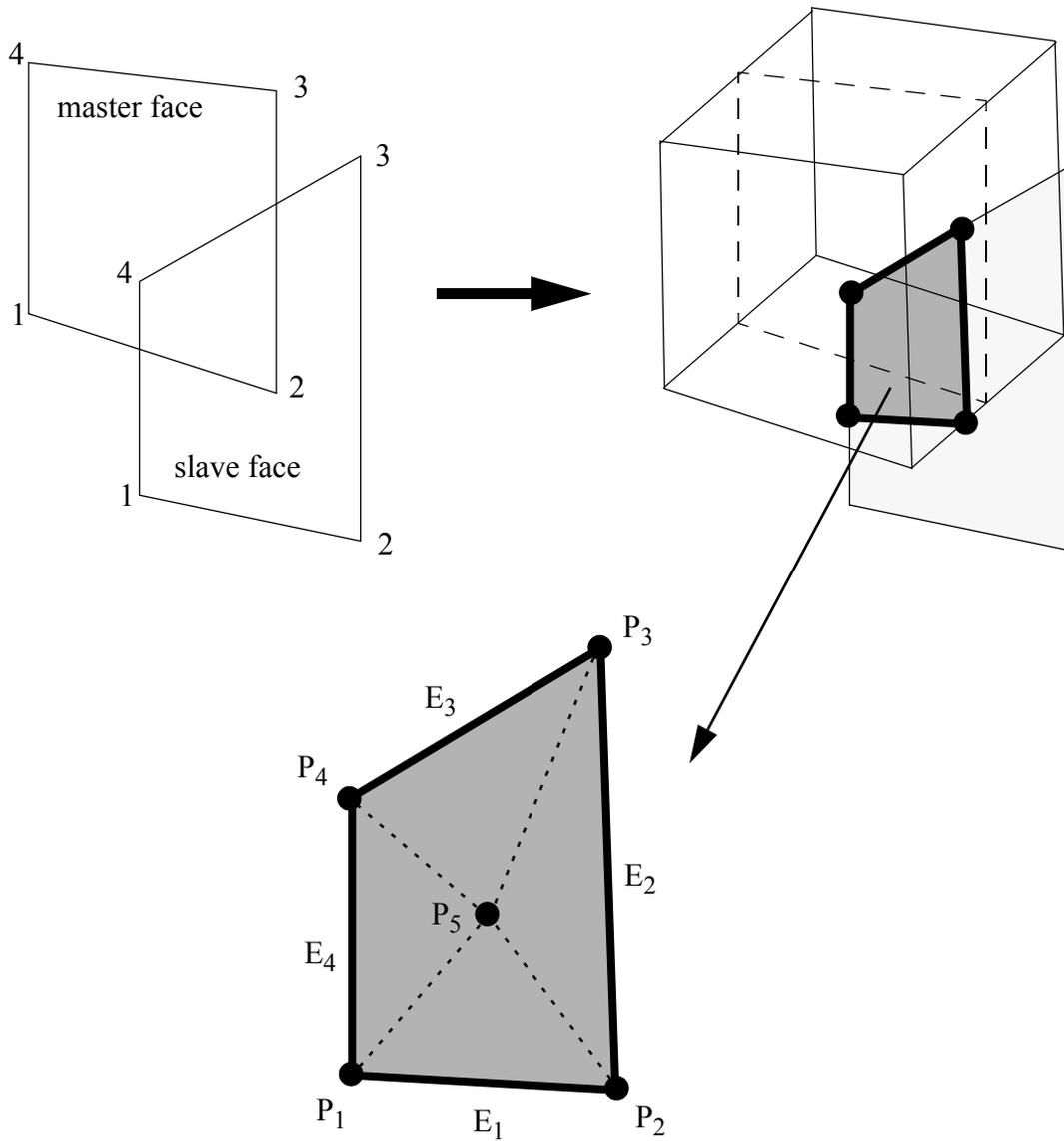
### 1.3.3 FaceFace\_Interactions

A FaceFace\_Interaction is returned as a set of data to the host code: a slave face (indicated by the Face\_Block ID and the index in that Face\_Block), a master face (indicated by the Face\_Block ID and the index in that Face\_Block), and data describing the interaction.

This interaction is only valid for faces of type QUADFACEL4 and TRIFACEL3. Consider the example shown in Figure 5. Here, two faces are in proximity and the FaceFace\_Interaction needs to be determined. The master face is transformed into a master volume by projecting the nodes in the +/- projection direction by the Search\_Normal\_Tolerance. By default, the projection direction for each node on the master face is the normal at that node (with or without smoothing). Optionally, the projection direction can be user-specified as a node attribute. This permits “mortarising” to be performed under user control (see Figure 6). Once the master face has been converted to a master volume, the intersection between the slave face and master volume is computed. This intersection is described with a closed polygon having  $N$  sides,  $E_n$ , and nodes,  $P_n$ . The points on the slave face that define the polygon are stored in the local coordinates of the slave face. These points are also computed as local coordinates of the master volume and projected onto the master face by setting  $\xi_3 = 0$  and then stored in the local coordinates of the master face. The resulting convex polygon can be triangularized by the host by calculating the centroid of the polygon,  $P_{N+1}$ , and connecting it to each node. Two additional arrays (of length  $N$ ) are defined that indicate with which edge, if any, of the master or slave face an edge of the polygon is coincident. Table 3 gives the Fortran layout of how the data are returned. It should be noted that only two local coordinates are returned. For triangular faces, the third local coordinate is simply unity minus the sum of the other two local coordinates.

Table 3 FaceFace\_Interaction Data for 3D

Location (Fortran Indexing)	Quantity
1	number of vertices (and edges), $N$
1+n	slave edge flag for edge $n=1,\dots,N$
(N+1)+n	master edge flag for edge $n=1,\dots,N$
(2*N+1)+4*(n-1)+1	Local Coordinate 1 on slave face for polygon node $X_n$ , $n=1,\dots,N$
(2*N+1)+4*(n-1)+2	Local Coordinate 2 on slave face for polygon node $X_n$ , $n=1,\dots,N$
(2*N+1)+4*(n-1)+3	Local Coordinate 1 on master face for polygon node $X_n$ , $n=1,\dots,N$
(2*N+1)+4*(n-1)+4	Local Coordinate 2 on master face for polygon node $X_n$ , $n=1,\dots,N$



Number of edges = 4  
 Master edge flag array = [0, 0, 0, 0]  
 Slave edge flag array = [0, 0, 3, 4]  
 Polygon nodes =  $P_1, P_2, P_3,$  and  $P_4$   
 Polygon centroid =  $P_5$

Figure 5 3D FaceFace\_Interactions

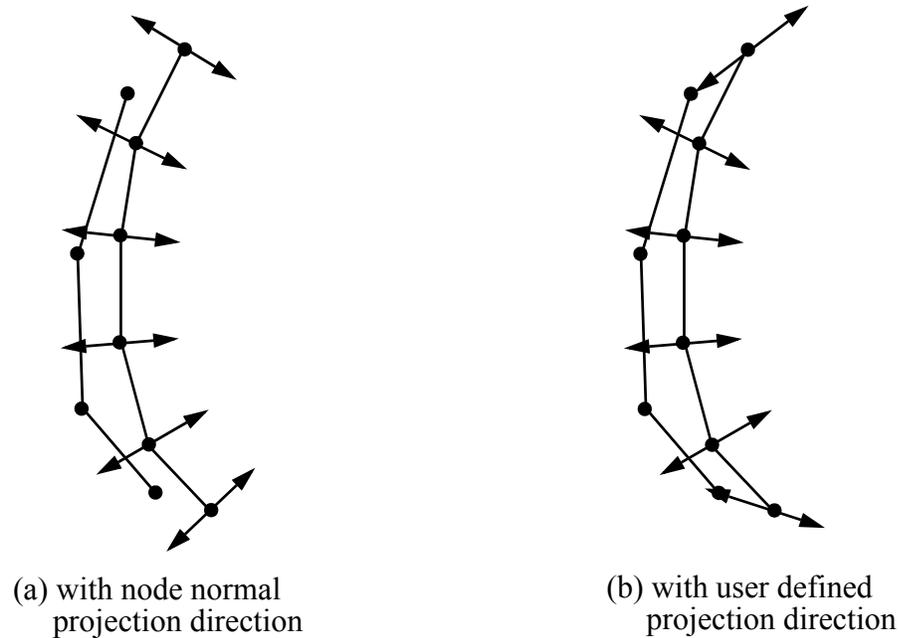


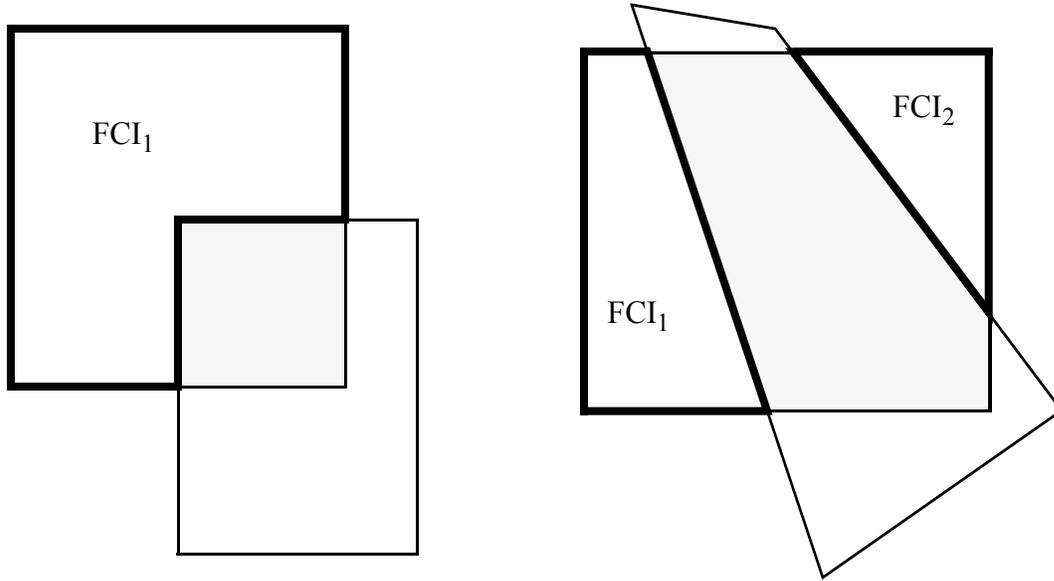
Figure 6 2D example of using `PROJECTION_DIRECTION` attribute to obtain user defined mortarising.

### 1.3.4 FaceCoverage\_Interactions

A `FaceCoverage_Interaction` is returned as a set of data to the host code: a face (indicated by the `Face_Block ID` and the index in that `Face_Block`) and data describing the interaction. Each `FaceCoverage_Interaction` is a closed polygon that describes an exposed (i.e., uncovered) portion of a face. The `FaceCoverage_Interaction` is computed by post-processing the `FaceFace_Interactions` for each face. A directed edge graph is constructed using the edges of the polygon from all the `FaceFace_Interactions` associated with each face and any portions of each face edge that are not part of a `FaceFace_Interaction` polygon. Closed polygons are then extracted from the directed edge graph to produce one or more `FaceCoverage_Interactions` for each face, as shown in Figure 7. Table 4 gives the Fortran layout of how the data are returned. For triangular faces, the third local coordinate is simply unity minus the sum of the other two local coordinates.

Table 4 `FaceCoverage_Interaction` Data for 3D

Location (Fortran Indexing)	Quantity
1	Number of vertices (and edges), $N$
$2*(n-1)+2$	Local Coordinate 1 for polygon node $P_n$ , $n=1,\dots,N$
$2*(n-1)+3$	Local Coordinate 2 for polygon node $P_n$ , $n=1,\dots,N$



(a) One FaceCoverage\_Interaction produced from post-processing the FaceFace\_Interactions.

(b) Two FaceCoverage\_Interactions produced from post-processing the FaceFace\_Interactions.

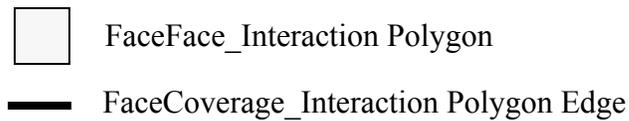


Figure 7 Post-processing of FaceFace\_Interactions to produce FaceCoverage\_Interactions.

### 1.3.5 ElementElement\_Interactions

An ElementElement\_Interaction is returned as a set of data to the host code: a slave element (indicated by the Element\_Block ID and the index in that Element\_Block), a master element (indicated by the Element\_Block ID and the index in that Element\_Block), and data describing the interaction. This interaction is only valid for elements of type CARTEISIANHEXELEMENTL8 and HEXELEMENTL8. Furthermore, at least one of the elements in every interaction must be a CARTEISIANHEXELEMENTL8. Table 5 gives the Fortran layout of how the data are returned. Currently, the only information returned for these interactions is the volume of the overlap.

Table 5 ElementElement\_Interaction Data for 3D

Location (Fortran Indexing)	Quantity
1	Volume of overlap between elements

## 1.4 Search Options

### 1.4.1 Multiple Interactions at a Node

By default, ACME defines only one interaction at a node. If potential interactions with more than one face are detected, ACME will return only one interaction (the best one, according to the algorithm used for competition between two interactions) to the host code. However, to get better behavior at a true corner of a body, multiple interactions with the faces surrounding the corner should be considered. Therefore, if desired, ACME can define multiple interactions at a node. When this feature is activated, the host code must specify an angle (in degrees) called SHARP\_NON\_SHARP\_ANGLE. If the angle between connected faces (computed as the angle between the normals to the faces, as shown in Figure 8) is greater than SHARP\_NON\_SHARP\_ANGLE, then an interaction will be defined for each face, instead of competition between the two to define one interaction. If the multiple interactions feature is not active, interactions with only one of two disconnected faces will be returned (see Figure 9). Interactions with disconnected faces will be returned to the host code regardless of the angle.

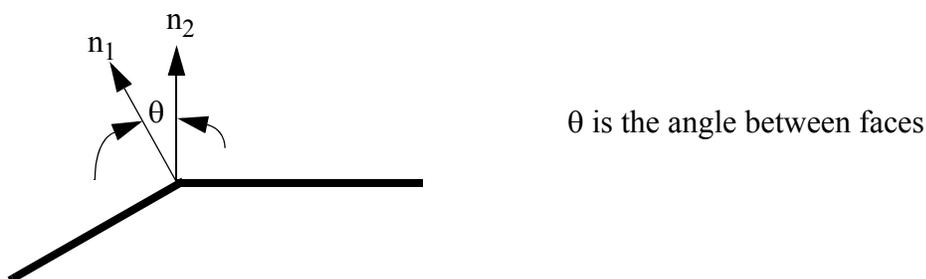


Figure 8 Definition of Angle Between Faces

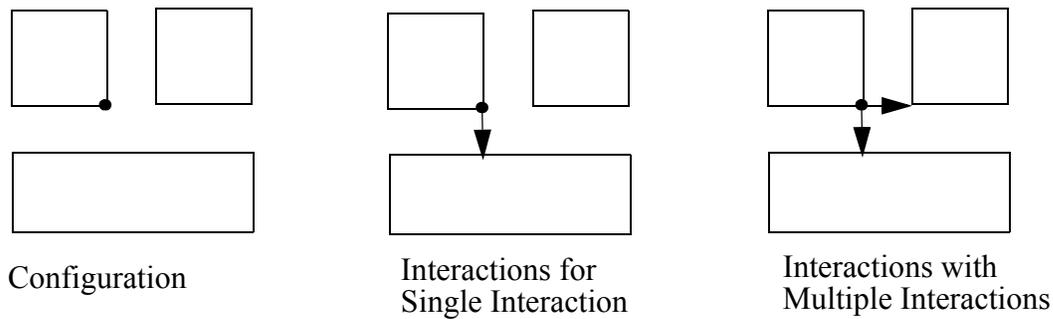


Figure 9 Interactions for Single vs. Multiple Interaction Definition

### 1.4.2 Normal Smoothing

As previously noted, a NodeFace\_Interaction consists of a contact point, a normal gap, a pushback direction, and a normal direction. The normal direction is an approximation of the normal to the surface at the contact point, which by default is simply the normal to the face. In some cases, however, it is necessary to have a continually varying normal without abrupt changes (e.g., when transitioning across an edge). The normal smoothing capability computes, if appropriate, a “smoothed” normal that varies continuously as a node transitions between faces. Smoothing occurs if the contact point is within a user-specified distance to the edge and if the included angle between the faces is less than the SHARP\_NON\_SHARP\_ANGLE (see Figure 10). The contact point, normal gap, and pushback direction are not modified by normal smoothing.



Figure 10 Normal Smoothing Across an Edge

When activating this feature, the host code must specify a SHARP\_NON\_SHARP\_ANGLE (in degrees), a normal smoothing distance, and a RESOLUTION\_METHOD for cases when a unique solution cannot be determined. If the angle between two faces is greater than the SHARP\_NON\_SHARP\_ANGLE, then the edge is considered SHARP and no smoothing will be done to the normal. The angle specified for normal smoothing must match the angle specified for multiple interactions if that capability is active.

The normal smoothing distance (SD) specifies the region over which normal smoothing occurs (see Figure 11). This distance is in isoparametric coordinates, so its value ranges from 0 to 1 (in theory), but for practical purposes, 0.5 is an upper bound.

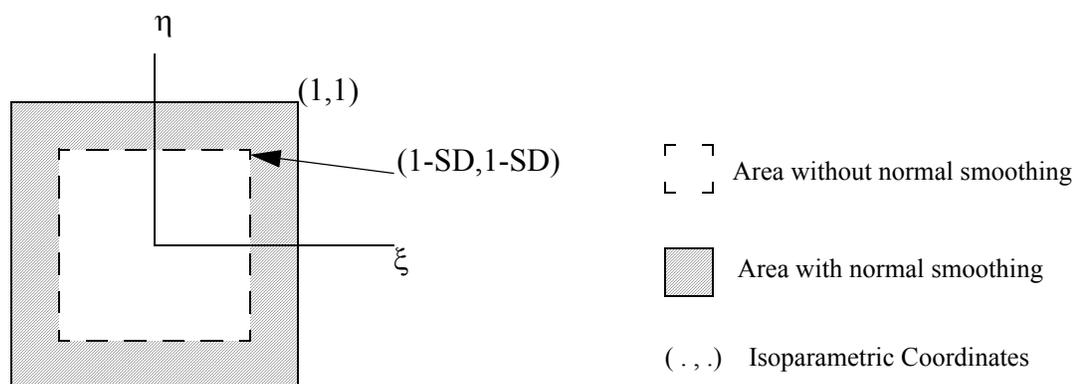


Figure 11 Region of Normal Smoothing for a QuadFaceL4

For the case when a unique solution does not exist for a smoothed normal, two resolution methods are provided: `USE_NODE_NORMAL` and `USE_EDGE_BASED_NORMAL`. To illustrate the differences between these two approaches, consider Figure 12. This example consists of five faces in the configuration shown, and uses a `SHARP_NON_SHARP_ANGLE` of 30 degrees. The angles between faces 1 and 5 and between faces 3 and 4 are greater than the `SHARP_NON_SHARP_ANGLE`, so the smoothing algorithm should not smooth between these faces. Smoothing is done between faces 1 and 2 and between faces 2 and 3, because the corresponding angles are less than 30 degrees. For points approaching the shared intersection of faces 1, 2, and 3, however, the two options ACME provides for determining the smoothed normal deliver different results. The `USE_NODE_NORMAL` option defines the normal at the intersection point to be the node normal and thus provides a continuously smooth normal in the region near the point. The problem with this approach in this particular case is that the node normal also includes the effects of faces 4 and 5, and thus effectively provides smoothing over the boundary between faces 1 and 5. Alternatively, the `USE_EDGE_BASED_NORMAL` option only considers smoothing between a pair of faces. This approach ensures that no smoothing occurs between faces 1 and 5, but it unfortunately can provide a different normal if we approach the intersection point from face 1 than if we approach the point from face 3. Therefore, the smoothed normal at the intersection point can be discontinuous, which can cause numerical problems in some applications. This feature will be addressed further as host codes gain experience on what approaches provide the best behavior.

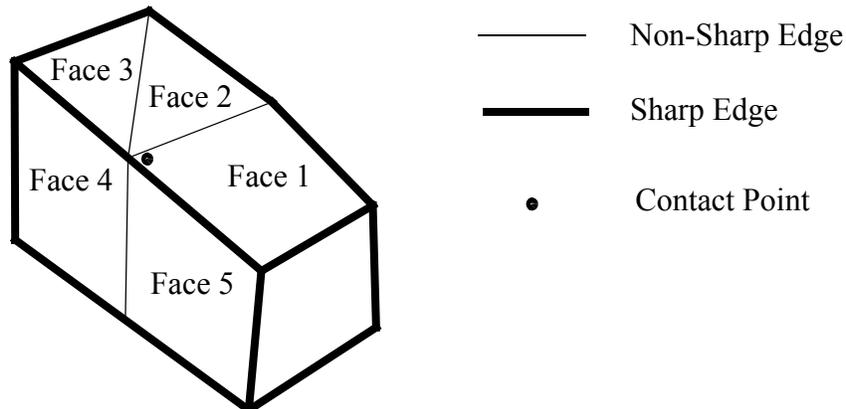


Figure 12 Illustration of Normal Smoothing Resolution

### 1.5 Gap Removal Enforcement

An optional gap removal enforcement is also included in ACME. Initial gaps often occur in meshes where curved geometries are discretized using varying mesh densities. The discretization error causes nodes from one (or more) surfaces to penetrate other surfaces. This initial gap can cause problems in explicit transient dynamic simulations (as well as other physics simulations) if the initial gap is large enough to cause interactions to be missed or if the initial gap is enforced on the first step, causing a large force. An effective method for avoiding these problems is to search for initial gaps and remove them in a strain-free manner (i.e., the initial topology is modified to remove the initial gaps). The enforcement object will compute the displacement correction needed to remove these initial gaps. Although it is not possible to have all nodes exactly on the faces of the other surface for curved geometries (it is an overconstrained problem), the gap removal enforcement seeks to satisfy the inequality that all gaps are non-negative with a minimum normal gap.

The gap removal enforcement should be used after performing a static 1-configuration search. The typical sequence for an explicit transient dynamic simulation would be:

- 1) Set the Search\_Data array appropriate for an initial gap search.
- 2) Perform a static 1-configuration search.
- 3) Call ContactGapRemoval::Compute\_Gap\_Removal.
- 4) Apply the displacement correction from step 3 to the topology.
- 5) Initialization (compute volume, mass, etc. using the modified topology).

Currently, ACME does not support the use of Gap Removal on meshes that include shell faces (SHELLQUADFACEL4 and SHELLTRIFACEL3).

## 1.6 Explicit Transient Dynamic Enforcement

An optional explicit transient dynamic enforcement capability is included in ACME. The algorithm was written assuming that the host code is integrating the equations of motion using a central difference time integrator. The topology, interactions, and configurations are taken directly from a ContactSearch object (i.e., the enforcement is dependent on a ContactSearch object). This capability takes as input the nodal masses from the host and returns the nodal forces that need to be applied.

The explicit transient dynamic enforcement can only be used in conjunction with the dynamic 2-configuration or dynamic augmented 2-configuration search methods. Following gap removal (if desired) and initialization, the continuation of the typical sequence for an explicit transient dynamic simulation would be:

- 6) Set the Search\_Data array appropriate for the analysis.
- 7) Time Step using
  - a) a dynamic or dynamic augmented 2-configuration search.
  - b) a ContactTDEnforcement enforcement.

Two parameters, KINEMATIC\_PARTITION and FRICTION\_MODEL\_ID, must be supplied by the host code for each possible entity pair. The KINEMATIC\_PARTITION pertains to the fraction of total momentum each contacting surface will absorb. For example, if surface 1 contacts surface 2 and the kinematic partition for surface 1 is  $k$ , then the kinematic partition for surface 2 with respect to surface 1 is  $1-k$ . Furthermore, if  $k$  is 1, then surface 1 acts as a “slave” to surface 2. The kinematic partition can either be a constant user-specified value (between 0 and 1) or the code will compute it for each interaction using the relations

$$\beta_1 = \frac{\rho_1 c_1}{\rho_1 c_1 + \rho_2 c_2} \quad (1)$$

$$\beta_2 = \frac{\rho_2 c_2}{\rho_1 c_1 + \rho_2 c_2} \quad (2)$$

where  $\beta_i$  is the kinematic partition,  $\rho_i$  is the density, and  $c_i$  is the wavespeed of the material for surface  $i$ , ( $i=1,2$ ).

The FRICTION\_MODEL\_ID refers to the particular friction model requested by the host code. There are currently nine friction models available: frictionless, constant Coulomb friction, tied, pressure dependent friction, velocity dependent friction, adhesion, spot weld, point weld, and cohesive zone. For NodeFace\_Interactions and NodeSurface\_Interactions, tied, frictionless, and frictional conditions can be enforced at a node. If these constraints are independent (e.g., three separate contact constraints at the corner of a block), the enforcement delivers the expected result. For conflicting con-

straints, a least-squares methodology is employed to resolve the forces required to effect the simultaneous interacting contact conditions.

### **1.7 Tied Kinematics Enforcement**

ACME provides an optional enforcement capability to compute the positions of nodes so that no relative motion occurs between a master face and a slave node. This enforcement only operates for a pure master-slave relationship (i.e., it does not work for symmetric cases). This enforcement was developed to serve as a remesh boundary condition for ALEGRA's SHISM capability but may have additional uses. It should be paired with a static 1\_configuration search, which only needs to be done once. The enforcement can then be called repeatedly to reposition the slave nodes using the interactions defined by the search, with the slave node position interpolated using the local coordinates and the positions of the nodes on the face.

### **1.8 Volume Transfer Enforcement**

An optional volume transfer enforcement capability is included in ACME. This enforcement provides facilities to transfer nodal and element data between two meshes. This data transfer is performed using linear interpolation between the master (donor) to slave (receiver) mesh for nodal variables. Element variables data is mapped between the two meshes using volume fraction weighting. A call to the volume transfer routine (see Section 7.2) provides both the transferred nodal and element variables along with the volume fraction on the receiving mesh filled by the donor mesh. This enforcement object requires that at least one of the meshes (either donor, receiver or both) consist of cartesian HEX8 elements.

### **1.9 Multiple Point Constraint (MPC) Enforcement**

An optional multiple point constraint (MPC) equation capability is included in ACME. This enforcement provides facilities to build MPC equations for pure master-slave enforcement of node-on-face interactions. The topology, interactions, and configurations are taken directly from a ContactSearch object (i.e., the enforcement is dependent on a ContactSearch object). The MPC algorithm should be paired with a static 1-configuration search, which only needs to be called once. Subsequent calls to the appropriate Contact-MPC functions (see Section 8.) build the constraint equations, get the number of equations and return the MPC data to the host code.

Calls to get the MPC equations return a list of the equations in terms of slave node ID, the ID of the master face and the IDs of the nodes attached to the face and their corresponding coefficients (cf. Section 8.). The scheme used for numbering the node and face IDs is user selectable being either the global ID supplied by the user when the search object was constructed or ACME's internal ID (cf. Section 8.). In parallel operation ACME's MPC enforcement will return to the calling processor all MPC equations for which the processor owns the face, the slave node, or has a ghost copy of the slave node. For this reason duplicate constraint equations may be returned when (in parallel) the calling processor owns the face and has a ghost of the slave node.

## 1.10 Errors

ACME will trap internal errors whenever possible and return gracefully to the host code. ACME will *never* try to recover from an error; it will simply return control to the host code. The host code, therefore, has the final decision of how to proceed. At the moment an internal error is detected, ACME will immediately return to the host code without attempting to finish processing or attempting to ensure its internal data are consistent. As a result, it is essential that the host code check for errors. Interactions may not be reasonable if an internal error was encountered.

Errors are reported in two ways. First, all public access functions that could encounter an error return a `ContactErrorCode` (an enumeration in the `ContactSearch` header file). This error return code will be globally synchronized (i.e., all processors will return the same value).

The current enumeration for error codes is:

```
enum ContactErrorCode{
    NO_ERROR = 0,
    ID_NOT_FOUND,
    UNKNOWN_TYPE,
    INVALID_ID,
    INVALID_DATA,
    UNIMPLEMENTED_FUNCTION,
    ZOLTAN_ERROR,
    EXODUS_ERROR,
    INVALID_INTERACTION,
    INTERNAL_ERROR };
```

The return value is meant as an easy check for the host code to determine if an error occurred on any processor. It does not specify which processor encountered the error, nor does it return a real description of the error or the ID (if appropriate) to determine on what entity the error occurred (e.g., which unimplemented function was called or, possibly in the future, which face has a negative area). ACME does not normally write any data to the standard output or error files (`stdout` or `stderr`). Instead, ACME provides functions to extract detailed error information line by line, which the host code can then direct to its own output files as desired. Each line is limited to 80 characters.

## 1.11 Plotting

ACME can be built with a compile-time option to include an ExodusII plotting capability. The host code is responsible for creating the ExodusII file, including the name and location of the plot file. It is also responsible for closing the file after ACME writes its data. Because ACME writes double precision data, this file must be created with the ExodusII parameter `ICOMPWS` set to 8.

If the host code desires a plot file from ACME, it *must* create a new file for each time step. This capability is primarily intended as a debugging tool and is not envisioned for use in production calculations. Since the host code specifies the mesh topology and has access to

the interactions, it has the ability to include the interaction data in its normal plotting functionality as it sees fit.

The mesh coordinates for each plot file are always taken as those in the current configuration. The displacements are the differences between the predicted and current coordinates if the predicted coordinates have been specified; otherwise the displacements are set to zero. Each Face\_Block is treated as an element block (TRI3 for TRIFACEL3, TRI6 for TRIFACEQ6, and SHELL for QUADFACEL4 and QUADFACEQ8), as are Element\_Blocks. Additional element blocks, one for each edge type, are created to represent the edges (BAR for LineEdgeL2 and BAR3 for LineEdgeQ3). An additional TRI3 element block is created to represent the FaceFace\_Interactions. An additional BAR element block is created to represent the FaceCoverage\_Interactions. Because ExodusII does not support node blocks, all the nodes are output without their associated Node\_Block. Shell faces are plotted in their lofted configuration.

### 1.11.1 Search Data Plot Variables

Plot output data consists of search and enforcement object variables. Global, nodal and element search data are presented in this section. The search data global output variables are listed in Table 6.

Table 6 Search Data Global Variables for ExodusII Output

Name	Description
num_nf_interactions	total number of NodeFace_Interactions
num_ns_interactions	total number of NodeSurface_Interactions
num_ff_interactions	total number of FaceFace_Interactions
num_fc_interactions	total number of FaceCoverage_Interactions
num_ee_interactions	total number of ElementElement_Interactions
mult_interaction_status	flag indicating if multiple interactions is on/off
norm_smoothing_status	flag indicating if normal smoothing is on/off
smoothing_angle	SHARP_NON_SHARP_ANGLE for normal smoothing and multiple interactions
smoothing_length	SD for normal smoothing
smoothing_resolution	RESOLUTION_METHOD for normal smoothing

The search data nodal output variables include both the nodal data (displacement and node normal) and the interactions (NodeFace\_Interactions and NodeSurface\_Interactions). The interactions are output for their associated node, rather than with the face. Currently, up to three interactions at a node can be output, with no meaning attached to their order. If a node has no interactions, all of the interaction data for that node will be zero. If a node has one interaction, the second and third sets of interaction data will all be zero, etc. Table 7 gives a description of all the nodal data written to the ExodusII file. (UNIX-style wildcard notation is used in this and subsequent tables. For example, displ[xyz] is shorthand for displx, displz, and displz.)

Table 7 Search Data Nodal Variables for ExodusII Output

Name	Description
displ[xyz]	X, Y & Z components of displacement
nnorm[xyz]	X, Y & Z components of the unit node normal
numcon	Number of kinematic constraints at the node
convec[xyz]	X, Y & Z components of kinematic constraint vector (provided by host)
face_id[123]	The ID of the face involved in interaction 1, 2, or 3 (0 if no interaction)
alg[123]	Algorithm used to define interaction 1, 2, or 3 (1=closest point projection for 1-configuration search, 2=closest point projection for 2-configuration search, 3=moving_intersection)
node_ek[123]	The node entity key for interaction 1, 2, or 3 (0 if no interaction)
gapcur[123]	The Gap arising from the current time step, not including any residual Gap
gapold[123]	The residual Gap from the previous time step for interaction 1, 2, or 3
pbdir[123][xyz]	X, Y, & Z components of the pushback direction for interaction 1, 2, or 3
ivec[123][xyz]	X, Y, & Z components of a vector that, when drawn from the node, gives the location of the interaction point for interaction 1, 2, or 3
norm[123][xyz]	X, Y, & Z components of the normal to the surface at the interaction point for interaction 1, 2, or 3

Table 7 Search Data Nodal Variables for ExodusII Output

Name	Description
pfnorm[123][xyz]	X, Y, & Z components of the physical face normal for the node for interaction 1, 2, or 3. (The physical face concept is used to obtain face to face contact without the full expense. A node on a flat surface will have only one physical face, while a node at the corner of a cube would have three physical faces (one for each of the three intersecting planes))
iveca[xyz]	X, Y, & Z components of a vector that, when drawn from the node, gives the location of the interaction point with an Analytic_Surface. This item is included only for problems with Analytic_Surfaces.
Global_ID	The global ID for the node supplied by the host code in the constructor
Primary_Owner	The processor that owns the node in the primary decomposition
Primary_Local_ID	The local ID for the node on the owning processor
Secondary_Owner	The processor that owns the node in the secondary decomposition
NodEnf[xyz]	X, Y, & Z components of a vector that is the force for ContactTDEnforcement and the displacement correction for ContactGapRemoval.

The “element” data actually consist of the element, face, and edge data (since they are output as element blocks). The FaceFace\_Interaction, FaceCoverage\_Interaction, and ElementElement\_Interaction data are also stored as element data. Table 8 gives the names and descriptions of the element data written to the ExodusII file.

Table 8 Search Data Element Variables for ExodusII Output

Name	Entity	Description
fnorm[xyz]	Faces	Unit face normal at centroid
curvature	Edges	0 = Unknown 1 = Convex 2 = Concave 3 = Concave with smoothing 4 = Convex with smoothing
angle_bf	Edges	The angle between the two faces connected to this edge. The value is zero if the edge is connected to only one face.
FFI[0-N]_FACE_ID	Faces	The ID of the master face involved in interaction 0, 1, ..., N=num_ffinteractions-1

Table 8 Search Data Element Variables for ExodusII Output

Name	Entity	Description
FFI[0-N]_NVERTS	Faces	The number of vertexes/edges in the polygon for interaction 0, 1, ..., N=num_ff_i_interactions-1
FFI[0-N]_SX[0-M]	Faces	The 1st local coordinate on the slave face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FFI[0-N]_SY[0-M]	Faces	The 2nd local coordinate on the slave face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FFI[0-N]_MX[0-M]	Faces	The 1st local coordinate on the master face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FFI[0-N]_MY[0-M]	Faces	The 2nd local coordinate on the master face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FFI[0-N]_EDGE[0-M]	Faces	The flag indicating coincidence with an edge on the slave face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FFI[0-N]_FLAG[0-M]	Faces	The flag indicating coincidence with an edge on the master face for interaction 0, 1, ..., N=num_ff_i_interactions-1 and vertex 0, 1, ..., M=nverts-1
FCI[0-N]_NVERTS	Faces	The number of vertexes/edges in the polygon for interaction 0, 1, ..., N=num_fci_interactions-1
FCI[0-N]_X[0-M]	Faces	The 1st local coordinate on the face for interaction 0, 1, ..., N=num_fci_interactions-1 and vertex 0, 1, ..., M=nverts-1
FCI[0-N]_Y[0-M]	Faces	The 2nd local coordinate on the face for interaction 0, 1, ..., N=num_fci_interactions-1 and vertex 0, 1, ..., M=nverts-1
PrimaryOwner	All	The processor that owns the entity in the primary decomposition
PrimaryLocalID	All	The local ID for the entity on the owning processor
SecondaryOwner	All	The processor that owns the entity in the secondary decomposition
Volume	Elems	The volume of the element

Table 8 Search Data Element Variables for ExodusII Output

Name	Entity	Description
NumVolVolOverlaps	Elms	The maximum number of volume-volume overlaps detected for an element, V
EEI[0-V]_ELEM_ID	Elms	The ID of an overlapping element (0 if none)
EEI[0-V]_VOLUME	Elms	The volume of the overlap between this element and the overlapping element (0 if none)
ElmEnf[1-5]	Elms	Element enforcement variables for volume overlap enforcement

### 1.11.2 Enforcement Data Plot Variables

The enforcement objects which provide ExodusII plot data include Gap Removal, Explicit Transient Dynamics, Tied Kinematics and Contact Volume Transfer. Depending on the enforcement, they provide nodal and element plot data. None of the enforcement objects provides global data. Nodal data for the Gap Removal, Explicit Transient Dynamics, Tied Kinematics and Contact Volume Transfer are presented in Table 9. Element data is provided only for the Contact Volume Transfer enforcement and these are presented in Table 10. As in the search, UNIX-style wildcard notation is used in this and subsequent tables.

Table 9 Enforcement Data Nodal Variables for ExodusII Output

Name	Enforcement	Description
Enfvar[xyz]	Gap Removal	Displacement increment needed to remove gap.
ENFVAR[xyz]	Explicit Transient Dynamics	Total contact force at the node.
ELMENF[1-N]	Contact Volume Transfer	The mapped element variable on the receiver mesh and its original value on the donor mesh where N element variables were supplied for transfer.
ELMENF[N+1]	Contact Volume Transfer	Volume fraction of receiver element filled with donor elements. Donor element values are set to zero.

Table 10 Search Data Element Variables for ExodusII Output

Name	Enforcement	Description
Enfvar[xyz]	Gap Removal	Displacement increment needed to remove gap.
ENFVAR[xyz]	Explicit Transient Dynamics	Total contact force at the node.
ENFVAR[xyz]	Tied Kine- matics	Final location of the node after moved to satisfy tied constraint.
NODENF[1-N]	Contact Vol- ume Transfer	The mapped nodal variable on the receiver mesh and the original nodal variable on the donor mesh where N nodal variables were supplied for transfer.

### 1.12 Restart Capabilities

ACME currently provides two options for restart. The first restart option is a binary data stream, where all of the data are packed into one array to be written to a restart file. This binary data stream can then be used with a special constructor to restore the objects to their original state. The second restart option allows a host code to extract node, edge and face restart variables one at a time to be output to a restart file. The variable-based restart requires the host code to call the basic constructor for the objects and then “implant” the restart variables into the object, which restores the objects to their states before the restart. Both restart methods currently require that neither the mesh topology nor the decomposition change. Eventually, the ability to restart with a different number of processors will be supported with the variable-based restart capability; it will not be supported with the binary stream restart function.

Currently, ACME only supports restart for meshes with shell faces (SHELLQUADFACEL4 and SHELLTRIFACEL3) using the variable-based restart capability.



## 2. Utility Functions

ACME provides various utility functions that are either independent of the search and enforcement objects or are identical for those objects. These include functions to obtain information about the current version of ACME, to extract information about errors encountered within the ACME algorithms, to extract data needed to restart ACME processing, and to create ExodusII plot files.

In each section delineating the ACME API functions (Sections 2, 3, 4, 5, and 6), the different forms for the C++, C, and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. On the other hand, the C and Fortran APIs, which in actuality have been combined into a single interface, are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address, not by value. For Fortran, there exists no capability to pass data by value, so simply specifying the name of the variable or array will allow it to be passed appropriately.

The `Search_Interface.h` and `Enforcement_Interface.h` header files, located in the ACME search and enforcement directories respectively, include the prototypes for the C and Fortran functions described in this chapter. The `ContactSearch.h` and `ContactEnforcement.h` files include the requisite C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in `ContactSearch.h`; these indicate the acceptable integral values that may be used in the C and Fortran APIs.

### 2.1 Version Information

Functions are provided to obtain the ACME version number and its release date and to check the compile-time compatibility of the ACME library and the host code with respect to the MPI library.

#### 2.1.1 Getting the Version ID

The following function returns the version of ACME, which is a character string of the form `x.yz`, where `x` is an integer representing the major version, `y` is an integer representing the minor version, and `z` is a letter representing the bug fix level. The initial release of this version of ACME will be `1.3a`, the first bug fix release will be `1.3b`, and so on. The prototype for this function is:

```

C++      const char* ACME_Version();

C        void FORTRAN(acme_version)( char* vers );

Fortran  acme_version( vers )

```

where

## Utility Functions

vers is an array of characters of length 80 (in C, 81 including the terminal '\n').

### 2.1.2 Getting the Version Date

The following function returns the release date for ACME, which is a character string of the form 'December 24, 2002' (the current release date). The prototype for this function is:

```
C++      const char* ACME_VersionDate();  
  
C        void FORTRAN(acme_versiondate)( char* vers_date );  
  
Fortran  acme_versiondate( vers_date )
```

where

vers\_date is an array of characters of length 80 (in C, 81 including the terminal '\n').

### 2.1.3 Checking Compatibility with MPI

The following function returns an error if the compilations of the host code and the ACME library are incompatible with respect to the MPI library. The host code should call this function with the host\_compile argument set to MPI\_COMPILE, which is defined in the ContactSearch header file to be 0 if CONTACT\_NO\_MPI is defined at compile time, and defined as 1 otherwise. This function will check for compatibility with the value of MPI\_COMPILE defined during compilation of the ACME library. The prototype for this function is:

```
C++      int ACME_MPI_Compatibility(int host_compile);  
  
C        void FORTRAN(acme_mpi_compatibility)  
          ( int* host_compile, int* error );  
  
Fortran  acme_mpi_compatibility( host_compile, error )
```

where

host\_compile is the value of MPI\_COMPILE used during compilation of the host code.  
error is the return error code for the C and Fortran APIs.

## 2.2 Errors

As discussed in Section 1.10, ACME attempts to trap internal errors whenever possible. There are C-style character strings that can be extracted to give a detailed description of what error(s) occurred during ACME processing for the search and enforcement objects. These strings are specific to the current processor. Therefore, each processor may have a different number of error messages. The error return code is synchronized in parallel so all processors return the same error code even if a processor did not encounter an error.

## 2.2.1 Getting the Number of Errors

The following functions, which are public member functions in the C++ API, determine how many error messages the current processor has written. The prototypes for these functions are:

```

C++      int ContactSearch::Number_of_Errors();
           int ContactTDEnforcement::Number_of_Errors();
           int ContactGapRemoval::Number_of_Errors();
           int ContactTiedKinematics::Number_of_Errors();
           int ContactVolumeTransfer::Number_of_Errors();

C        FORTRAN(number_of_search_errors)( int* num_errors );
           FORTRAN(number_of_td_errors)( int* num_errors );
           FORTRAN(number_of_gap_errors)( int* num_errors );
           FORTRAN(number_of_tied_errors)( int* num_errors );
           FORTRAN(number_of_voltrans_errors)( int* num_errors );

Fortran  number_of_search_errors( num_errors )
           number_of_td_errors( num_errors )
           number_of_gap_errors( num_errors )
           number_of_tied_errors( num_errors )
           number_of_voltrans_errors( num_errors )

```

where

num\_errors is the number of error messages that should be extracted by the host code.

## 2.2.2 Extracting Error Messages

The following functions, which are public member functions in the C++ API, can be used to extract the character strings for each error message on a processor (the number of which can be determined by the functions described in the previous section):

```

C++      const char* ContactSearch::Error_Message( int i );
           const char* ContactTDEnforcement::Error_Message( int i );
           const char* ContactGapRemoval::Error_Message( int i );
           const char* ContactTiedKinematics::Error_Message( int i );
           const char* ContactVolumeTransfer::Error_Message( int i );

C        FORTRAN(get_search_error_message)(
           int* i,
           char* message );
           FORTRAN(get_td_error_message)(
           int* i,
           char* message );
           FORTRAN(get_gap_error_message)(
           int* i,
           char* message );
           FORTRAN(get_tied_kin_error_message)(
           int* i,
           char* message );

```

## Utility Functions

```
FORTRAN(get_vol_tran_error_message) (
    int* i,
    char* message );
```

```
Fortran get_search_error_message( i, message )
get_td_error_message( i, message )
get_gap_error_message( i, message )
get_tied_kin_error_message( i, message )
get_vol_tran_error_message( i, message )
```

where

i is the Fortran index of the error message (i.e., 1 to Number\_of\_Errors(), or num\_errors for C and Fortran).  
message is an array of characters of length 80 (in C, 81 including the terminal '\n').

## 2.3 Binary Stream Restart Functions

ACME provides functionality to allow restart using a single binary stream of data for each ACME search or enforcement object. The host code is responsible for allocating the array to hold the data, calling the functions, and writing the data to a restart file. Upon restart, the host code should supply the binary data stream to the special constructors described in this section, which will restore the objects to their state before restart.

Currently, ACME does not support restarting analyses which contain shell faces (SHELLQUADFACEL4 and SHELLTRIFACEL3) using the binary stream restart capability. Restart with shells is supported through the variable-based restart functions.

### 2.3.1 Getting the Binary Restart Size

The following functions allow the host code to determine how much memory to allocate to store restart information for the search and enforcement objects. The return value is the number of double locations that are needed.

```
C++    int ContactSearch::Restart_Size();
        int ContactTDEnforcement::Restart_Size();
        int ContactGapRemoval::Restart_Size();
        int ContactTiedKinematics::Restart_Size();
        int ContactVolumeTransfer::Restart_Size();

C      FORTRAN(search_restart_size)( int* size );
        FORTRAN(td_enf_restart_size)( int* size );
        FORTRAN(gap_removal_restart_size)( int* size );
        FORTRAN(tied_kin_restart_size)( int* size );
        FORTRAN(vol_tran_restart_size)( int* size );

Fortran search_restart_size( size )
        td_enf_restart_size( size )
        gap_removal_restart_size( size )
        tied_kin_restart_size( size )
```

```
vol_tran_restart_size( size )
```

where

size is the number of double locations that are needed for the restart data.

### 2.3.2 Extracting the Binary Restart Data

The following functions allow the host code to extract all the information needed to initialize an ACME object to its current state.

```
C++    ContactErrorCode
        ContactSearch::Extract_Restart_Data (
            double* restart_data);
        ContactErrorCode
        ContactTDEnforcement::Extract_Restart_Data (
            double* restart_data);
        ContactErrorCode
        ContactGapRemoval::Extract_Restart_Data (
            double* restart_data);
        ContactErrorCode
        ContactTiedKinematics::Extract_Restart_Data (
            double* restart_data);
        ContactErrorCode
        ContactVolumeTransfer::Extract_Restart_Data (
            double* restart_data);

C      FORTRAN(search_extract_restart) (
            double* restart_data,
            int* error);
        FORTRAN(td_enf_extract_restart) (
            double* restart_data,
            int* error);
        FORTRAN(gap_removal_extract_restart) (
            double* restart_data,
            int* error);
        FORTRAN(tied_kin_extract_restart) (
            double* restart_data,
            int* error);
        FORTRAN(vol_tran_extract_restart) (
            double* restart_data,
            int error);

Fortran search_extract_restart( restart_data, error)
        td_enf_extract_restart( restart_data, error)
        gap_removal_extract_restart( restart_data, error)
        tied_kin_extract_restart( restart_data, error)
        vol_tran_extract_restart( restart_data, error)
```

where

## Utility Functions

restart\_data is an array of type double. The length of this array is obtained from the function Restart\_Size() (see the previous section).  
error is the return error code for the C and Fortran APIs.

### 2.3.3 Constructing Objects Upon Restart

Note, ACME does not enforce the requirement that host code global ids be identical across a restart. This allows the host code to renumber nodes and faces when performing a restart (due to adaptivity or element birth/death) but also requires that the host code supply the host code global id numbering to ACME when performing a restart. As noted above, a second constructor is available to allow for restarts from the binary data stream provided by the Extract\_Restart\_Data functions described in Section 2.3.2:

```
C++      ContactSearch::ContactSearch (
            const double* restart_data,
            const int* node_global_ids,
            const int* face_global_ids,
            const MPI_Comm& mpi_communicator,
            ContactErrorCode& error );
ContactTDEnforcement::ContactTDEnforcement (
            ContactSearch* search,
            double* restart_data,
            int* error );
ContactGapRemoval::ContactGapRemoval (
            ContactSearch* search,
            double* restart_data,
            int* error );
ContactTiedKinematics::ContactTiedKinematics (
            ContactSearch* search,
            double* restart_data,
            int* error );
ContactVolumeTransfer::ContactVolumeTransfer (
            ContactSearch* search,
            double* restart_data,
            int* error );

C        FORTRAN(build_search_restart) (
            double* restart_data,
            int* node_global_ids,
            int* face_global_ids,
            int* mpi_communicator,
            int* error );

FORTRAN(build_td_enf_restart) (
            double* restart_data,
            int* error );
FORTRAN(build_gap_removal_restart) (
            double* restart_data,
            int* error );
FORTRAN(build_tied_kin_restart) (
            double* restart_data,
```

```

        int* error );
FORTRAN(build_vol_tran_restart(
        double* restart_data,
        int* error );

Fortran build_search_restart(
        restart_data,
        node_global_ids,
        face_global_ids,
        mpi_communicator,
        error )
build_td_enf_restart(
        restart_data,
        error )
build_gap_removal_restart(
        restart_data,
        error )
build_tied_kin_restart(
        restart_data,
        error )
build_vol_tran_restart(
        restart_data,
        error )

```

where

`restart_data` is an array of type `double`. The length of this array is obtained from the function `Restart_Size()` (see the previous section).

`node_global_ids` is an array (whose length is twice the total number of nodes in all `Node_Blocks`) containing the host code ID for each node. Each host code ID consists of two integers. For node `N`, the array index `2*N` contains the most significant word and the index `2*N+1` contains the least significant word. The IDs for the first `Node_Block` are listed first in the array, followed by the IDs for each of the other `Node_Blocks` in order (if applicable).

`face_global_ids` is an array (whose length is twice the total number of faces in all `Face_Blocks`) containing the host code ID for each face. Each host code ID consists of two integers. For face `N`, the array index `2*N` contains the most significant word and the index `2*N+1` contains the least significant word. The IDs for the first `Face_Block` are listed first in the array, followed by the IDs for each of the other `Face_Blocks` in order (if applicable).

`mpi_communicator` is an MPI communicator if ACME was built for a parallel and is simply a dummy `int` otherwise.

`search` is the associated `ContactSearch` object for this enforcement object. This is hidden in the C and Fortran APIs because only one search object is allowed.

`error` is the error return code that will reflect any errors that were detected.

## 2.4 Variable-Based Restart Functions

The variable-based restart functions allow a host code to extract all the restart variables from the ACME objects variable by variable. This set of functions will eventually allow restarts on different numbers of processors, although that capability is not supported in this release. There are no separate constructors for this type of restart. Instead, the traditional constructor is used and then the variable-based data are “implanted.” ACME does

support restarting analyses which contain shell faces (SHELLQUADFACEL4 and SHELLTRIFACEL3) using the variable-based restart capability.

### 2.4.1 Obtaining the Number of General Restart Variables

These functions supply the number of general variables from each search and enforcement object that need to be written to (or read from) a restart file. A general variable is a variable that is true for an entire search or enforcement, and is not related to any specific node, edge, or face.

```

C++      int
           ContactSearch::Number_General_Restart_Variables();
           int
           ContactTDEnforcement::Number_General_Restart_Variables();
           int
           ContactGapRemoval::Number_General_Restart_Variables();
           int
           ContactTiedKinematics::Number_General_Restart_Variables();
           int
           ContactVolumeTransfer::Number_General_Restart_Variables();

C        FORTRAN( search_num_general_rsvars )( int* num_nvars );
           FORTRAN( td_enf_num_general_rsvars )( int* num_nvars );
           FORTRAN( gap_removal_num_general_rsvars ) ( int* num_nvars
);
           FORTRAN( tied_kin_num_general_rsvars )( int* num_nvars );
           FORTRAN( vol_tran_num_general_rsvars )( int* num_nvars );

Fortran  search_num_general_rsvars( num_vars )
           td_enf_num_general_rsvars( num_nvars )
           gap_removal_num_general_rsvars( num_nvars )
           tied_kin_num_general_rsvars( num_nvars )
           vol_tran_num_general_rsvars( num_nvars )

```

where

num\_nvars is the number of general restart variables

### 2.4.2 Obtaining the Number of Nodal Restart Variables

These functions supply the number of nodal variables from each search and enforcement object that need to be written to (or read from) a restart file.

```

C++      int
           ContactSearch::Number_Nodal_Restart_Variables();
           int
           ContactTDEnforcement::Number_Nodal_Restart_Variables();
           int
           ContactGapRemoval::Number_Nodal_Restart_Variables();
           int
           ContactTiedKinematics::Number_Nodal_Restart_Variables();
           int

```

```
ContactVolumeTransfer::Number_Nodal_Restart_Variables();
```

```
C   FORTRAN( search_num_node_rsvars )( int* num_nvars );
      FORTRAN( td_enf_num_node_rsvars )( int* num_nvars );
      FORTRAN( gap_removal_num_node_rsvars ) ( int* num_nvars );
      FORTRAN( tied_kin_num_node_rsvars )( int* num_nvars );
      FORTRAN( vol_tran_num_node_rsvars )( int* num_nvars );
```

```
Fortran search_num_node_rsvars( num_nvars )
          td_enf_num_node_rsvars( num_nvars )
          gap_removal_num_node_rsvars( num_nvars )
          tied_kin_num_node_rsvars( num_nvars )
          vol_tran_num_node_rsvars( num_nvars )
```

where

num\_nvars is the number of nodal restart variables

### 2.4.3 Obtaining the Number of Edge Restart Variables

These functions supply the number of edge variables from each search and enforcement object that need to be written to (or read from) a restart file. Currently, there are no edge-based restart variables, so the ambiguity of how to handle the issue that edges are internally generated, not supplied by the host code, is deferred until edge-based restart variables are required. These functions are included here to complete the API.

```
C++   int
        ContactSearch::Number_Edge_Restart_Variables();
        int
        ContactTDEnforcement::Number_Edge_Restart_Variables();
        int
        ContactGapRemoval::Number_Edge_Restart_Variables();
        int
        ContactTiedKinematics::Number_Edge_Restart_Variables();
        int
        ContactVolumeTransfer::Number_Edge_Restart_Variables();
```

```
C   FORTRAN( search_num_edge_rsvars )( int* num_evars );
      FORTRAN( td_enf_num_edge_rsvars )( int* num_evars );
      FORTRAN( gap_removal_num_edge_rsvars ) ( int* num_evars );
      FORTRAN( tied_kin_num_edge_rsvars )( int* num_evars );
      FORTRAN( vol_tran_num_edge_rsvars )( int* num_evars );
```

```
Fortran search_num_edge_rsvars( num_evars )
          td_enf_num_edge_rsvars( num_evars )
          gap_removal_num_edge_rsvars( num_evars )
          tied_kin_num_edge_rsvars( num_evars )
          vol_tran_num_edge_rsvars( num_evars )
```

where

num\_evars is the number of edge restart variables

### 2.4.4 Obtaining the Number of Face Restart Variables

These functions supply the number of face variables from each search and enforcement object that need to be written to (or read from) a restart file.

```

C++      int
            ContactSearch::Number_Face_Restart_Variables();
            int
            ContactTDEnforcement::Number_Face_Restart_Variables();
            int
            ContactGapRemoval::Number_Face_Restart_Variables();
            int
            ContactTiedKinematics::Number_Face_Restart_Variables();
            int
            ContactVolumeTransfer::Number_Face_Restart_Variables();

C        FORTRAN( search_num_face_rsvars )( int* num_fvars );
            FORTRAN( td_enf_num_face_rsvars )( int* num_fvars );
            FORTRAN( gap_num_face_rsvars ) ( int* num_fvars );
            FORTRAN( tied_kin_num_face_rsvars )( int* num_fvars );
            FORTRAN( vol_tran_num_face_rsvars )( int* num_fvars );

Fortran  search_num_face_rsvars( num_fvars )
            td_enf_num_face_rsvars( num_fvars )
            gap_num_face_rsvars( num_fvars )
            tied_kin_num_face_rsvars( num_fvars )
            vol_tran_num_face_rsvars( num_fvars )

```

where

num\_fvars is the number of face restart variables

### 2.4.5 Obtaining the Number of Element Restart Variables

These functions supply the number of element variables from each search and enforcement object that need to be written to (or read from) a restart file.

```

C++      int ContactSearch::Number_Element_Restart_Variables();
            int
            ContactTDEnforcement::Number_Element_Restart_Variables();
            int
            ContactGapRemoval::Number_Element_Restart_Variables();
            int
            ContactTiedKinematics::Number_Element_Restart_Variables();
            int
            ContactVolumeTransfer::Number_Element_Restart_Variables();

C        FORTRAN( search_num_element_rsvars )( int* num_fvars );
            FORTRAN( td_enf_num_element_rsvars )( int* num_fvars );

```

```

FORTRAN( gap_num_element_rsvars ) ( int* num_fvars );
FORTRAN( tied_kin_num_element_rsvars ) ( int* num_fvars );
FORTRAN( vol_tran_num_element_rsvars ) ( int* num_fvars );

```

```

Fortran search_num_element_rsvars( num_fvars )
td_enf_num_element_rsvars( num_fvars )
gap_num_element_rsvars( num_fvars )
tied_kin_num_element_rsvars( num_fvars )
vol_tran_num_element_rsvars( num_fvars )

```

where

num\_fvars is the number of element restart variables

## 2.4.6 Extracting the General Restart Variables

These functions extract the general variables that are required for restart for the search and enforcement objects.

```

C++ ContactErrorCode
ContactSearch::Extract_General_Restart_Variable(
    double* variable_data );
ContactErrorCode
ContactTDEnforcement::Extract_General_Restart_Variable(
    double* variable_data );
ContactErrorCode
ContactGapRemoval::Extract_General_Restart_Variable(
    double* variable_data );
ContactErrorCode
ContactTiedKinematics::Extract_General_Restart_Variable(
    double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Extract_General_Restart_Variable(
    double* variable_data );

```

```

C FORTRAN(search_extract_general_rsvars)(
    double* variable_data,
    int* error );
FORTRAN(td_extract_general_rsvars)(
    double* variable_data,
    int* error );
FORTRAN(gap_extract_general_rsvars)(
    double* variable_data,
    int* error );
FORTRAN(tied_kin_extract_general_rsvars)(
    double* variable_data,
    int* error );
FORTRAN(vol_tran_extract_general_rsvars)(
    double* variable_data,
    int* error );

```

```

Fortran search_extract_general_rsvars(

```

## Utility Functions

```
        variable_data,  
        error )  
td_extract_general_rsvars(  
    variable_data,  
    error )  
gap_extract_general_rsvars(  
    variable_data,  
    error )  
tied_kin_extract_general_rsvars(  
    variable_data,  
    error )  
vol_tran_extract_general_rsvars(  
    variable_data,  
    error )
```

where

`variable_data` is an array of type `double`. The length of the array is the number of global variables as given by the functions described above.  
`error` is the return error code for the C and Fortran APIs.

### 2.4.7 Implanting the General Restart Variables

These functions implant the general variables that are required for restart for the search and enforcement objects.

```
C++    ContactErrorCode  
        ContactSearch::Implant_General_Restart_Variable(  
            double* variable_data );  
        ContactErrorCode  
        ContactTDEnforcement::Implant_General_Restart_Variable(  
            double* variable_data );  
        ContactErrorCode  
        ContactGapRemoval::Implant_General_Restart_Variable(  
            double* variable_data );  
        ContactErrorCode  
        ContactTiedKinematics::Implant_General_Restart_Variable(  
            double* variable_data );  
        ContactErrorCode  
        ContactVolumeTransfer::Implant_General_Restart_Variable(  
            double* variable_data );  
  
C        FORTRAN(search_implant_general_rsvars)(  
            double* variable_data,  
            int* error );  
        FORTRAN(td_implant_general_rsvars)(  
            double* variable_data,  
            int* error );  
        FORTRAN(gap_implant_general_rsvars)(  
            double* variable_data,  
            int* error );  
        FORTRAN(tied_kin_implant_general_rsvars)(  
            double* variable_data,
```

```

        int* error );
FORTRAN(voltrans_implant_general_rsvars)(
        double* variable_data,
        int* error );

Fortran search_implant_general_rsvars(
        variable_data,
        error )
td_implant_general_rsvars(
        variable_data,
        error )
gap_implant_general_rsvars(
        variable_data,
        error )
tied_kin_implant_general_rsvars(
        variable_data,
        error )
voltrans_implant_general_rsvars(
        variable_data,
        error )

```

where

variable\_data is an array of type double. The length of the array is the number of global variables as given by the functions described above.  
error is the return error code for the C and Fortran APIs.

## 2.4.8 Extracting the Nodal Restart Variables

These functions extract the nodal variables, one by one, that are required for restart.

```

C++ ContactErrorCode
ContactSearch::Extract_Nodal_Restart_Variable(
        int variable_number,
        double* variable_data );
ContactErrorCode
ContactTDEnforcement::Extract_Nodal_Restart_Variable(
        int variable_number,
        double* variable_data );
ContactErrorCode
ContactGapRemoval::Extract_Nodal_Restart_Variable(
        int variable_number,
        double* variable_data );
ContactErrorCode
ContactTiedKinematics::Extract_Nodal_Restart_Variable(
        int variable_number,
        double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Extract_Nodal_Restart_Variable(
        int variable_number,
        double* variable_data );

```

## Utility Functions

```
C      FORTRAN(search_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
FORTRAN(td_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
FORTRAN(gap_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
FORTRAN(tied_kin_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
FORTRAN(vol_tran_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
```

```
Fortran search_extract_node_rsvars (
        variable_number,
        variable_data,
        error )
td_extract_node_rsvars (
        variable_number,
        variable_data,
        error )
gap_extract_node_rsvars (
        variable_number,
        variable_data,
        error )
tied_kin_extract_node_rsvars) (
        int variable_number,
        double* variable_data,
        int* error );
vol_tran_extract_node_rsvars (
        int variable_number,
        double* variable_data,
        int* error );
```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
variable\_data is an array of type double. The length of the array is given by the number of nodes in the surface topology for this processor (as supplied in the constructor).  
error is the return error code for the C and Fortran APIs.

### 2.4.9 Implanting the Nodal Restart Variables

These functions implant the nodal variables, one by one, that are required for restart.

```

C++ ContactErrorCode
ContactSearch::Implant_Nodal_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTDEnforcement::Implant_Nodal_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactGapRemoval::Implant_Nodal_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTiedKinematics::Implant_Nodal_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Implant_Nodal_Restart_Variable(
    int variable_number,
    double* variable_data );

C FORTRAN(search_implant_node_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(td_implant_node_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(gap_implant_node_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(tied_kin_implant_node_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(vol_tran_implant_node_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );

Fortran search_implant_node_rsvars(
    variable_number,
    variable_data,
    error )
td_implant_node_rsvars(
    variable_number,
    variable_data,
    error )
gap_implant_node_rsvars(
    variable_number,
    variable_data,
    error )

```

## Utility Functions

```
tied_kin_implant_node_rsvars(  
    variable_number,  
    variable_data,  
    error )  
vol_tran_implant_node_rsvars(  
    variable_number,  
    variable_data,  
    error )
```

where

`variable_number` is the variable number (using Fortran indexing; i.e, from 1 to N).  
`variable_data` is an array of type double. The length of the array is given by the number of nodes in the surface topology for this processor (as supplied in the constructor).

### 2.4.10 Extracting the Edge Restart Variables

These functions extract the edge variables, one by one, that are required for restart. As previously mentioned, there are currently no edge-based restart variables, so these functions will not be used in this version of ACME.

```
C++    ContactErrorCode  
        ContactSearch::Extract_Edge_Restart_Variable(  
            int variable_number,  
            double* variable_data );  
        ContactErrorCode  
        ContactTDEnforcement::Extract_Edge_Restart_Variable(  
            int variable_number,  
            double* variable_data );  
        ContactErrorCode  
        ContactGapRemoval::Extract_Edge_Restart_Variable(  
            int variable_number,  
            double* variable_data );  
        ContactErrorCode  
        ContactTiedKinematics::Extract_Edge_Restart_Variable(  
            int variable_number,  
            double* variable_data );  
        ContactErrorCode  
        ContactVolumeTransfer::Extract_Edge_Restart_Variable(  
            int variable_number,  
            double* variable_data );  
  
C      FORTRAN(search_extract_edge_rsvars)(  
            int variable_number,  
            double* variable_data,  
            int* error );  
        FORTRAN(td_extract_edge_rsvars)(  
            int variable_number,  
            double* variable_data,  
            int* error );  
        FORTRAN(gap_extract_edge_rsvars)(  
            int variable_number,
```

```

        double* variable_data,
        int* error );
FORTRAN(tied_kin_extract_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(vol_tran_extract_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );

Fortran search_extract_edge_rsvars(
    variable_number,
    variable_data,
    error )
td_extract_edge_rsvars(
    variable_number,
    variable_data,
    error )
gap_extract_edge_rsvars(
    variable_number,
    variable_data,
    error )
tied_kin_extract_edge_rsvars(
    variable_number,
    variable_data,
    error )
vol_tran_extract_edge_rsvars(
    variable_number,
    variable_data,
    error )

```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
variable\_data is an array of type double. The length of the array is given by the number of edges in the surface topology for this processor.

### 2.4.11 Implanting the Edge Restart Variables

These functions implant the edge variables, one by one, that are required for restart. As previously mentioned, there are currently no edge-based restart variables so these functions will not be used in this version of ACME.

```

C++ ContactErrorCode
ContactSearch::Implant_Edge_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTDEnforcement::Implant_Edge_Restart_Variable(
    int variable_number,
    double* variable_data );

```

## Utility Functions

```
ContactErrorCode
ContactGapRemoval::Implant_Edge_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTiedKinematics::Implant_Edge_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Implant_Edge_Restart_Variable(
    int variable_number,
    double* variable_data );
```

```
C FORTRAN(search_implant_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(td_implant_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(gap_implant_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(tied_kin_implant_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(vol_tran_implant_edge_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
```

```
Fortran search_implant_edge_rsvars(
    variable_number,
    variable_data,
    error )
td_implant_edge_rsvars(
    variable_number,
    variable_data,
    error )
gap_implant_edge_rsvars(
    variable_number,
    variable_data,
    error )
tied_kin_implant_edge_rsvars(
    variable_number,
    variable_data,
    error )
vol_tran_implant_edge_rsvars(
    variable_number,
    variable_data,
    error )
```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
 variable\_data is an array of type double. The length of the array is given by the number of edges in the surface topology for this processor.

### 2.4.12 Extracting the Face Restart Variables

These functions extract the face variables, one by one, that are required for restart.

```

C++      ContactErrorCode
            ContactSearch::Extract_Face_Restart_Variable(
                int variable_number,
                double* variable_data );
            ContactErrorCode
            ContactTDEnforcement::Extract_Face_Restart_Variable(
                int variable_number,
                double* variable_data );
            ContactErrorCode
            ContactGapRemoval::Extract_Face_Restart_Variable(
                int variable_number,
                double* variable_data );
            ContactErrorCode
            ContactTiedKinematics::Extract_Face_Restart_Variable(
                int variable_number,
                double* variable_data );
            ContactErrorCode
            ContactVolumeTransfer::Extract_Face_Restart_Variable(
                int variable_number,
                double* variable_data );

C        FORTRAN(search_extract_face_rsvars)(
                int variable_number,
                double* variable_data,
                int* error );
            FORTRAN(td_extract_face_rsvars)(
                int variable_number,
                double* variable_data,
                int* error );
            FORTRAN(gap_extract_face_rsvars)(
                int variable_number,
                double* variable_data,
                int* error );
            FORTRAN(tied_kin_extract_face_rsvars)(
                int variable_number,
                double* variable_data,
                int* error );
            FORTRAN(vol_tran_extract_face_rsvars)(
                int variable_number,
                double* variable_data,
                int* error );
  
```

```
Fortran search_extract_face_rsvars(  
    variable_number,  
    variable_data,  
    error )  
td_extract_face_rsvars(  
    variable_number,  
    variable_data,  
    error )  
gap_extract_face_rsvars(  
    variable_number,  
    variable_data,  
    error )  
tied_kin_extract_face_rsvars(  
    variable_number,  
    variable_data,  
    error )  
vol_tran_extract_face_rsvars(  
    variable_number,  
    variable_data,  
    error )
```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
variable\_data is an array of type double. The length of the array is given by the number of faces in the surface topology for this processor (as supplied in the constructor).

### 2.4.13 Implanting the Face Restart Variables

These functions implant the face variables, one by one, that are required for restart.

```
C++ ContactErrorCode  
ContactSearch::Implant_Face_Restart_Variable(  
    int variable_number,  
    double* variable_data );  
ContactErrorCode  
ContactTDEnforcement::Implant_Face_Restart_Variable(  
    int variable_number,  
    double* variable_data );  
ContactErrorCode  
ContactGapRemoval::Implant_Face_Restart_Variable(  
    int variable_number,  
    double* variable_data );  
ContactErrorCode  
ContactTiedKinematics::Implant_Face_Restart_Variable(  
    int variable_number,  
    double* variable_data );  
ContactErrorCode  
ContactVolumeTransfer::Implant_Face_Restart_Variable(  
    int variable_number,  
    double* variable_data );
```

```

C      FORTRAN(search_implant_face_rsvars) (
          int variable_number,
          double* variable_data,
          int* error );
FORTRAN(td_implant_face_rsvars) (
          int variable_number,
          double* variable_data,
          int* error );
FORTRAN(gap_implant_face_rsvars) (
          int variable_number,
          double* variable_data,
          int* error );
FORTRAN(tied_kin_implant_face_rsvars) (
          int variable_number,
          double* variable_data,
          int* error );
FORTRAN(vol_tran_implant_face_rsvars) (
          int variable_number,
          double* variable_data,
          int* error );

```

```

Fortran search_implant_face_rsvars (
          variable_number,
          variable_data,
          error )
td_implant_face_rsvars (
          variable_number,
          variable_data,
          error )
gap_implant_face_rsvars (
          variable_number,
          variable_data,
          error )
tied_kin_implant_face_rsvars (
          variable_number,
          variable_data,
          error )
vol_tran_implant_face_rsvars (
          variable_number,
          variable_data,
          error )

```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
variable\_data is an array of type double. The length of the array is given by the number of faces in the surface topology for this processor (as supplied in the constructor).

#### 2.4.14 Extracting the Element Restart Variables

These functions extract the element variables, one by one, that are required for restart.

## Utility Functions

```
C++ ContactErrorCode
ContactSearch::Extract_Element_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTDEnforcement::Extract_Element_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactGapRemoval::Extract_Element_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTiedKinematics::Extract_Element_Restart_Variable(
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Extract_Element_Restart_Variable(
    int variable_number,
    double* variable_data );

C FORTRAN(search_extract_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(td_extract_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(gap_extract_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(tied_kin_extract_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(vol_tran_extract_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );

Fortran search_extract_element_rsvars(
    variable_number,
    variable_data,
    error )
td_extract_element_rsvars(
    variable_number,
    variable_data,
    error )
gap_extract_element_rsvars(
    variable_number,
    variable_data,
    error )
```

```

tied_kin_extract_element_rsvars (
    variable_number,
    variable_data,
    error )
vol_tran_extract_element_rsvars (
    variable_number,
    variable_data,
    error )

```

where

variable\_number is the variable number (using Fortran indexing; i.e, from 1 to N).  
variable\_data is an array of type double. The length of the array is given by the number of elements in the surface topology for this processor (as supplied in the constructor).

### 2.4.15 Implanting the Element Restart Variables

These functions implant the element variables, one by one, that are required for restart.

```

C++    ContactErrorCode
ContactSearch::Implant_Element_Restart_Variable (
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTDEnforcement::Implant_Element_Restart_Variable (
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactGapRemoval::Implant_Element_Restart_Variable (
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactTiedKinematics::Implant_Element_Restart_Variable (
    int variable_number,
    double* variable_data );
ContactErrorCode
ContactVolumeTransfer::Implant_Element_Restart_Variable (
    int variable_number,
    double* variable_data );

C      FORTRAN(search_implant_element_rsvars) (
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(td_implant_element_rsvars) (
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(gap_implant_element_rsvars) (
    int variable_number,
    double* variable_data,
    int* error );

```

## Utility Functions

```
FORTRAN(tied_kin_implant_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
FORTRAN(vol_tran_implant_element_rsvars)(
    int variable_number,
    double* variable_data,
    int* error );
```

```
Fortran search_implant_element_rsvars(
    variable_number,
    variable_data,
    error )
td_implant_element_rsvars(
    variable_number,
    variable_data,
    error )
gap_implant_element_rsvars(
    variable_number,
    variable_data,
    error )
tied_kin_implant_element_rsvars(
    variable_number,
    variable_data,
    error )
vol_tran_implant_element_rsvars(
    variable_number,
    variable_data,
    error )
```

where

`variable_number` is the variable number (using Fortran indexing; i.e, from 1 to N).  
`variable_data` is an array of type double. The length of the array is given by the number of elements in the surface topology for this processor (as supplied in the constructor).

### 2.4.16 Completing a Variable-Based Restart

These functions *must* be called after constructing an ACME object and implanting the restart variables with the functions described previously. These functions restore each ACME object to its state prior to restart. After these functions have been called, normal calculations can resume.

```
C++ ContactErrorCode
ContactSearch::Complete_Restart();
ContactErrorCode
ContactTDEnforcement::Complete_Restart();
ContactErrorCode
ContactGapRemoval::Complete_Restart();
ContactErrorCode
ContactTiedKinematics::Complete_Restart();
ContactErrorCode
```

```

ContactVolumeTransfer::Complete_Restart();

C      FORTRAN(search_complete_restart)( int* error );
        FORTRAN(td_enf_complete_restart)( int* error );
        FORTRAN(gap_complete_restart)( int* error );
        FORTRAN(tied_kin_complete_restart)( int* error );
        FORTRAN(vol_tran_complete_restart)( int* error );

Fortran search_complete_restart( error )
        td_enf_complete_restart( error )
        gap_complete_restart( error )
        tied_kin_complete_restart( error )
        vol_tran_complete_restart( error )

```

where

error is the return error code for the C and Fortran APIs.

## 2.5 Creating an Exodus Plot File of the Search & Enforcement Data

ACME has the ability to write an ExodusII file that contains the full search topology and all of the interaction data, including enforcement results. This function can be used only if ACME was built with ExodusII support (a compile time option). See Section 1.11 for a detailed description of the data written to the ExodusII file. The host code is required to actually open and close the ExodusII file, so it must choose the name and location for the file. This file must be opened with ICOMPWS=8. The ExodusII ID is then passed to ACME, which writes the topology and the results data. Only one plot step can be written to each file. The number of variables in the database depends on the number of interaction types currently active in the search object (which can change each time step).

The prototype for this capability is:

```

C++      ContactErrorCode ContactSearch::Exodus_Output (
            int exodus_id,
            double time );

C      FORTRAN(exodus_output)(
            int* exodus_id,
            double* time,
            int* error );

Fortran exodus_output (
            exodus_id,
            time,
            error )

```

where

exodus\_id is the integer database ID returned by the ExodusII library from an ex\_create call.  
time is the time value for the “results” to be written to the ExodusII file.  
error is the return error code for the C and Fortran APIs.



### 3. Search Functions

This section describes functions that construct and operate on ContactSearch “objects.” For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. There are no static variables, so an arbitrary number of objects may be simultaneously active. In the C and Fortran APIs, these functions create and operate on a ContactSearch “object,” only one of which is currently allowed. Functions are provided to allow destruction of the ContactSearch object and creation of a new object at any point. Multiple objects can be supported in the future if the need ever arises.

There are two constructors for the ContactSearch object. The first, described in this section, is intended for general use, while the second, described in Section 2, is used to construct a search object using data read in from a previously generated restart file. The ContactSearch object is neither copy-able nor assignable.

In each section delineating the ACME API functions (Sections 2, 3, 4, 5, and 6), the different forms for the C++, C, and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. On the other hand, the C and Fortran APIs, which in actuality have been combined into a single interface, are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address, not by value. For Fortran, there exists no capability to pass data by value, so simply specifying the name of the variable or array will allow it to be passed appropriately.

The Search\_Interface.h and Enforcement\_Interface.h header files, located in the ACME search and enforcement directories respectively, include the prototypes for the C and Fortran functions described in this chapter. The ContactSearch.h and ContactEnforcement.h files include the requisite C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in ContactSearch.h; these indicate the acceptable integral values that may be used in the C and Fortran APIs.

#### 3.1 Creating a ContactSearch Object

There is one general constructor for the ContactSearch object. A second constructor for restart is described in Section 2.3.2. The prototype for the general constructor is:

```
C++ ContactSearch::ContactSearch(
    int dimensionality,
    int number_of_states,
    int number_of_entity_keys,
    int number_of_node_blocks,
    const ContactSearch::ContactNode_Type*
        node_block_types,
    const int* number_of_nodes_in_blocks,
    const int* node_exodus_ids,
    const int* node_global_ids,
```

## Search Functions

```
int number_of_face_blocks,  
const ContactSearch::ContactFace_Type*  
    face_block_types,  
const int* number_of_faces_in_blocks,  
const int* face_global_ids,  
const int* face_connectivity,  
int number_of_element_blocks,  
const ContactSearch::ContactElement_Type*  
    element_block_types,  
const int* number_of_elements_in_blocks,  
const int* element_global_ids,  
const int* element_connectivity,  
int number_of_nodal_comm_partners,  
const int* nodal_comm_proc_ids,  
const int* number_of_nodes_to_partner,  
const int* communication_nodes,  
const MPI_Comm& mpi_communicator,  
ContactErrorCode& error );
```

```
C      FORTRAN(build_search)(  
        int* dimensionality,  
        int* number_of_states,  
        int* number_of_entity_keys,  
        int* number_of_node_blocks,  
        int* node_block_types,  
        int* number_of_nodes_in_blocks,  
        int* node_exodus_ids,  
        int* node_global_ids,  
        int* number_of_face_blocks,  
        int* face_block_types,  
        int* number_of_faces_in_blocks,  
        int* face_global_ids,  
        int* face_connectivity,  
        int* number_of_element_blocks,  
        int* element_block_types,  
        int* number_of_elements_in_blocks,  
        int* element_global_ids,  
        int* element_connectivity,  
        int* number_of_nodal_comm_partners,  
        int* nodal_comm_proc_ids,  
        int* number_of_nodes_to_partner,  
        int* communication_nodes,  
        int* mpi_communicator,  
        int* error );
```

```
Fortran build_search(  
    dimensionality,  
    number_of_states,  
    number_of_entity_keys,  
    number_of_node_blocks,  
    node_block_types,  
    number_of_nodes_in_blocks,  
    node_exodus_ids,  
    node_global_ids,
```

```

    number_of_face_blocks,
    face_block_types,
    number_of_faces_in_blocks,
    face_global_ids,
    face_connectivity,
    number_of_element_blocks,
    element_block_types,
    number_of_elements_in_blocks,
    element_global_ids,
    element_connectivity,
    number_of_nodal_comm_partners,
    nodal_comm_proc_ids,
    number_of_nodes_to_partner,
    communication_nodes,
    mpi_communicator,
    error );

```

where:

`dimensionality` is the number of spatial coordinates in the topology. Note: We are only supporting three dimensions in this release. Two-dimensional support will be added in the future.

`number_of_states` is the number of states the host code requests to be stored. A value of 1 implies that the `ContactSearch` object can not back up to an older state. A value of 2 will imply the `ContactSearch` object can back up to one old state, etc. For this release, this value *must* be 1.

`number_of_entity_keys` is the number of entity keys that will be used. This is currently the sum of the number of `Face_Blocks` and the number of `Analytic_Surfaces`.

`number_of_node_blocks` is the number of `Node_Blocks` in the topology. The first `Node_Block` contains the nodes connected to the faces specified in the `Face_Blocks`; additional `Node_Blocks` may contain other nodes that the host code needs to search against the faces.

`node_block_types` is an array (of length `number_of_node_blocks`) describing the type of nodes in each `Node_Block`. The current enumeration for this type in the C++ API is:

```
enum ContactSearch::ContactNode_Type{ NODE=1 };
```

`number_of_nodes_in_blocks` is an array (of length `number_of_node_blocks`) that gives the number of nodes in each `Node_Block`.

`node_exodus_ids` is an array (whose length is the total number of nodes in all `Node_Blocks`) containing the Exodus ID for each node. The IDs for the first `Node_Block` are listed first in the array, followed by the IDs for each of the other `Node_Blocks` in order (if applicable).

`node_global_ids` is an array (whose length is twice the total number of nodes in all `Node_Blocks`) containing the host code ID for each node. Each host code ID consists of two integers. For node  $N$ , the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. The IDs for the first `Node_Block` are listed first in the array, followed by the IDs for each of the other `Node_Blocks` in order (if applicable).

`number_of_face_blocks` is the number of `Face_Blocks` in the topology.

`face_block_types` is an array (of length `number_of_face_blocks`) describing the type of faces in each `Face_Block`. The current enumeration for this type in the C++ API is:

```
enum ContactSearch::ContactFace_Type{QUADFACEL4=1,
    QUADFACEQ8=2, TRIFACEL3=3, TRIFACEQ6=4,
    SHELLQUADFACEL4=5, SHELLTRIFACEL3=6};
```

`number_of_faces_in_blocks` is an array (of length `number_of_face_blocks`) that gives the number of faces in each `Face_Block`.

`face_global_ids` is an array (whose length is twice the total number of faces in all `Face_Blocks`) containing the host code ID for each face. Each host code ID consists of two integers. For

## Search Functions

face N, the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. The IDs for the first Face\_Block are listed first in the array, followed by the IDs for each of the other Face\_Blocks in order (if applicable).

face\_connectivity is a one-dimensional array that gives the connectivity (using Fortran indexing in the first Node\_Block) for each face. The connectivity of each face is contiguous in memory and follows the ExodusII conventions for node order. The arrangement of this array may change when multiple Node\_Blocks containing nodes related to faces are supported. Note that if the faces of shells are included, then both sides of the shell must be given as faces: once with a clockwise numbering and once with a counter-clockwise numbering.

number\_of\_element\_blocks is the number of Element\_Blocks in the topology.

element\_block\_types is an array (of length number\_of\_element\_blocks) describing the type of elements in each Element\_Block. The current enumeration for this type in the C++ API is:

```
enum ContactSearch::ContactElement_Type
    {CARTESIANHEXELEMENTL8=1, HEXELEMENTL8=1};
```

number\_of\_elements\_in\_blocks is an array (of length number\_of\_element\_blocks) that gives the number of elements in each Element\_Block.

element\_global\_ids is an array (whose length is twice the total number of elements in all Element\_Blocks) containing the host code ID for each element. Each host code ID consists of two integers. For element N, the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. The IDs for the first Element\_Block are listed first in the array, followed by the IDs for each of the other Element\_Blocks in order (if applicable).

element\_connectivity is a one-dimensional array that gives the connectivity (using Fortran indexing in the first Node\_Block) for each element. The connectivity of each element is contiguous in memory and follows the ExodusII conventions for node order. The arrangement of this array may change when multiple Node\_Blocks containing nodes related to elements are supported.

number\_of\_nodal\_comm\_partners is the number of processors that share nodes with the topology supplied to ACME on the current processor.

nodal\_comm\_proc\_ids is an array (of length number\_of\_nodal\_comm\_partners) that lists the processor IDs that share nodes with the topology supplied to ACME on the current processor.

number\_of\_nodes\_to\_partner is an array (of length number\_of\_nodal\_comm\_partners) that gives the number of nodes shared with each processor in nodal\_comm\_proc\_ids.

communication\_nodes is an array that lists the nodes in the topology supplied to ACME that are shared, grouped by processor in the order specified in nodal\_comm\_proc\_ids.

mpi\_communicator is an MPI\_Communicator.

error is the error code. This reflects any errors detected during execution of this method. A non-zero result indicates an error has occurred.

If the ACME library is built in pure serial mode (i.e., CONTACT\_NO\_MPI is defined during compilation), then number\_of\_nodal\_comm\_partners should be set to 0 and dummy pointers can be supplied for nodal\_comm\_proc\_ids, number\_of\_nodes\_to\_partner, and communication\_nodes. Furthermore, any integer value can be used for mpi\_communicator, which is ignored.

### 3.2 Updating a Search Object

If the topology of the search object changes (due to either element birth/death or dynamic load balancing), then the search object's topology can be updated with the interaction information preserved across the topology change. It is assumed that the dimensionality, number\_of\_states, number\_of\_entity\_keys, and the number and type of entity blocks stays

the same. *This capability currently does not work if shell face types are present.* The interface to update a search object's topology is:

```
C++      void ContactSearch::UpdateSearch(
            const int* number_of_nodes_in_blocks,
            const int* node_exodus_ids,
            const int* node_global_ids,
            const int* number_of_faces_in_blocks,
            const int* face_global_ids,
            const int* face_connectivity,
            const int* number_of_elements_in_blocks,
            const int* element_global_ids,
            const int* element_connectivity,
            int number_of_nodal_comm_partners,
            const int* nodal_comm_proc_ids,
            const int* number_of_nodes_to_partner,
            const int* communication_nodes,
            const int* number_of_exported_nodes,
            const int* exported_nodes_global_ids,
            const int* exported_nodes_proc_ids,
            const int* number_of_exported_faces,
            const int* exported_faces_global_ids,
            const int* exported_faces_proc_ids,
            const int* number_of_exported_elements,
            const int* exported_elements_global_ids,
            const int* exported_elements_proc_ids,
            ContactErrorCode& error );
```

```
C        FORTRAN(update_search) (
            int* number_of_nodes_in_blocks,
            int* node_exodus_ids,
            int* node_global_ids,
            int* number_of_faces_in_blocks,
            int* face_global_ids,
            int* face_connectivity,
            int* number_of_elements_in_blocks,
            int* element_global_ids,
            int* element_connectivity,
            int* number_of_nodal_comm_partners,
            int* nodal_comm_proc_ids,
            int* number_of_nodes_to_partner,
            int* communication_nodes,
            int* number_of_exported_nodes,
            int* exported_nodes_global_ids,
            int* exported_nodes_proc_ids,
            int* number_of_exported_faces,
            int* exported_faces_global_ids,
            int* exported_faces_proc_ids,
            int* number_of_exported_elements,
            int* exported_elements_global_ids,
            int* exported_elements_proc_ids,
            int* error );
```

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```
Fortran update_search(  
    number_of_nodes_in_blocks,  
    node_exodus_ids,  
    node_global_ids,  
    number_of_faces_in_blocks,  
    face_global_ids,  
    face_connectivity,  
    number_of_elements_in_blocks,  
    element_global_ids,  
    element_connectivity,  
    number_of_nodal_comm_partners,  
    nodal_comm_proc_ids,  
    number_of_nodes_to_partner,  
    communication_nodes,  
    number_of_exported_nodes,  
    exported_nodes_global_ids,  
    exported_nodes_proc_ids,  
    number_of_exported_faces,  
    exported_faces_global_ids,  
    exported_faces_proc_ids,  
    number_of_exported_elements,  
    exported_elements_global_ids,  
    exported_elements_proc_ids,  
    error );
```

where:

`number_of_nodes_in_blocks` is an array (of length `number_of_node_blocks`) that gives the number of nodes in each `Node_Block`.

`node_exodus_ids` is an array (whose length is the total number of nodes in all `Node_Blocks`) containing the Exodus ID for each node. The IDs for the first `Node_Block` are listed first in the array, followed by the IDs for each of the other `Node_Blocks` in order (if applicable).

`node_global_ids` is an array (whose length is twice the total number of nodes in all `Node_Blocks`) containing the host code ID for each node. Each host code ID consists of two integers. For node  $N$ , the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. The IDs for the first `Node_Block` are listed first in the array, followed by the IDs for each of the other `Node_Blocks` in order (if applicable).

`number_of_faces_in_blocks` is an array (of length `number_of_face_blocks`) that gives the number of faces in each `Face_Block`.

`face_global_ids` is an array (whose length is twice the total number of faces in all `Face_Blocks`) containing the host code ID for each face. Each host code ID consists of two integers. For face  $N$ , the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. The IDs for the first `Face_Block` are listed first in the array, followed by the IDs for each of the other `Face_Blocks` in order (if applicable).

`face_connectivity` is a one-dimensional array that gives the connectivity (using Fortran indexing in the first `Node_Block`) for each face. The connectivity of each face is contiguous in memory and follows the ExodusII conventions for node order. The arrangement of this array may change when multiple `Node_Blocks` containing nodes related to faces are supported.

`number_of_elements_in_blocks` is an array (of length `number_of_element_blocks`) that gives the number of elements in each `Element_Block`.

`element_global_ids` is an array (whose length is twice the total number of elements in all `Element_Blocks`) containing the host code ID for each element. Each host code ID consists of two integers. For element  $N$ , the array index  $2*N$  contains the most significant

word and the index  $2*N+1$  contains the least significant word. The IDs for the first Element\_Block are listed first in the array, followed by the IDs for each of the other Element\_Blocks in order (if applicable).

element\_connectivity is a one-dimensional array that gives the connectivity (using Fortran indexing in the first Node\_Block) for each element. The connectivity of each element is contiguous in memory and follows the ExodusII conventions for node order. The arrangement of this array may change when multiple Node\_Blocks containing nodes related to elements are supported.

number\_of\_nodal\_comm\_partners is the number of processors that share nodes with the topology supplied to ACME on the current processor.

nodal\_comm\_proc\_ids is an array (of length number\_of\_nodal\_comm\_partners) that lists the processor IDs that share nodes with the topology supplied to ACME on the current processor.

number\_of\_nodes\_to\_partner is an array (of length number\_of\_nodal\_comm\_partners) that gives the number of nodes shared with each processor in nodal\_comm\_proc\_ids.

communication\_nodes is an array that lists the nodes in the topology supplied to ACME that are shared, grouped by processor in the order specified in nodal\_comm\_proc\_ids.

number\_of\_exported\_nodes is the number of nodes that are in both the old and new topology but reside on a different processor in the new topology. This is only applicable for dynamic load balancing. Note: For this release, dynamic load balancing is not yet supported.

exported\_nodes\_host\_ids is an array (of length  $2*\text{number\_of\_exported\_nodes}$ ) containing the host code ID for each node that is in both the old and new topology but resides on a different processor in the new topology. Each host code ID consists of two integers. For node N, the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. This is only applicable for dynamic load balancing.

exported\_nodes\_proc\_ids is an array (of length number\_of\_exported\_nodes) containing the processor ID of the processor that contains the node in the new topology. This is only applicable for dynamic load balancing.

number\_of\_exported\_faces is the number of faces that are in both the old and new topology but reside on a different processor in the new topology. This is only applicable for dynamic load balancing. Note: For this release, dynamic load balancing is not yet supported.

exported\_faces\_host\_ids is an array (of length  $2*\text{number\_of\_exported\_faces}$ ) containing the host code ID for each face that is in both the old and new topology but resides on a different processor in the new topology. Each host code ID consists of two integers. For face N, the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. This is only applicable for dynamic load balancing.

exported\_faces\_proc\_ids is an array (of length number\_of\_exported\_faces) containing the processor ID of the processor that contains the face in the new topology. This is only applicable for dynamic load balancing.

number\_of\_exported\_elements is the number of elements that are in both the old and new topology but reside on a different processor in the new topology. This is only applicable for dynamic load balancing. Note: For this release, dynamic load balancing is not yet supported.

exported\_elements\_host\_ids is an array (of length  $2*\text{number\_of\_exported\_elements}$ ) containing the host code ID for each element that is in both the old and new topology but resides on a different processor in the new topology. Each host code ID consists of two integers. For element N, the array index  $2*N$  contains the most significant word and the index  $2*N+1$  contains the least significant word. This is only applicable for dynamic load balancing.

exported\_elements\_proc\_ids is an array (of length number\_of\_exported\_elements) containing the processor ID of the processor that contains the element in the new topology. This is only applicable for dynamic load balancing.

error is the error code. This reflects any errors detected during execution of this method. A non-zero result indicates an error has occurred.

If the ACME library is built in pure serial mode (i.e., CONTACT\_NO\_MPI is defined during compilation), then number\_of\_nodal\_comm\_partners should be set to 0 and dum-

my pointers can be supplied for `nodal_comm_proc_ids`, `number_of_nodes_to_partner`, and `communication_nodes`.

### 3.3 Search\_Data Array

As described in Section 1.1.5, `Search_Data` is a three-dimensional Fortran-ordered array for specifying entity pair data. The first index in the array refers to the data parameter, and the next two indexes refer to the keys for the two entities for which that parameter is applicable.

#### 3.3.1 Checking the Search\_Data Array Size

The following interface allows for checking the size of `Search_Data` expected by ACME. This is intended to be a check by the host code to ensure that ACME and the host code have a consistent view of the `Search_Data` array.

```
C++      ContactErrorCode ContactSearch::Check_Search_Data_Size(  
          int size_data_per_pair,  
          int number_of_entity_keys );  
  
C        FORTRAN(check_search_data_size)(  
          int* size_data_per_pair,  
          int* number_of_entity_keys,  
          int* error );  
  
Fortran  check_search_data_size(  
          size_data_per_pair,  
          number_of_entity_keys,  
          error )
```

where

`size_data_per_pair` is the number of data parameters for each entity pair (currently 3).  
`number_of_entity_keys` is the number of entity keys.  
`error` is the return error code for the C and Fortran APIs.

#### 3.3.2 Setting Values in the Search\_Data Array

The following interface allows the host code to specify the `Search_Data` array (see Section 1.1.5), which must be set prior to calling any of the search algorithms. This function can be called at any time to change values in the `Search_Data` array (e.g., to change tolerances).

```
C++      void ContactSearch::Set_Search_Data(  
          const double* search_data);  
  
C        FORTRAN(set_search_data)(  
          double* search_data );  
  
Fortran  set_search_data(  
          search_data )
```

where

search\_data is an array of double precision values for the Search\_Data (see Section 1.1.5).

### 3.4 Analytic\_Surfaces

ACME supports the determination of interactions of nodes with Analytic\_Surfaces. Currently, the only supported Analytic\_Surfaces are a plane, a sphere, and two types of cylinders (one for a container and one for a post). The types of Analytic\_Surfaces supported will be expanded in the future. The ACME ID for an Analytic\_Surface is the number of face blocks plus the order in which the surface was created.

The current enumeration for Analytic\_Surface\_Type in the C++ API is:

```
enum ContactSearch::AnalyticSurface_Type{
    PLANE=1, SPHERE=2, CYLINDER_INSIDE=3, CYLINDER_OUTSIDE=4 };
```

#### 3.4.1 Adding an Analytic\_Surface

The interface to add an Analytic\_Surface is:

```
C++      ContactErrorCode ContactSearch::Add_Analytic_Surface(
           ContactSearch::AnalyticSurface_Type as_type,
           const double* as_data );

C        FORTRAN(add_analytic_surface) (
           int* as_type,
           double* as_data,
           int* error );

Fortran  add_analytic_surface (
           as_type,
           as_data,
           error )
```

where

as\_type is the type of the analytic surface from the ContactSearch::AnalyticSurface\_Type enum.  
as\_data is an array dependent on the type of surface being added. The Analytic\_Surface PLANE is described by a point and a normal vector. The Analytic\_Surface SPHERE is described by its center and a radius. Two types of cylindrical surfaces are supported: CYLINDER\_INSIDE & CYLINDER\_OUTSIDE. CYLINDER\_INSIDE is intended as a cylindrical container which will define interactions to keep all nodes inside the cylinder. CYLINDER\_OUTSIDE is intended as a post which will define interactions to keep all nodes outside the cylinder. Both types of cylindrical surfaces are described by a center point, an axial direction, and a length (see Figure 13). Table 11 gives a complete description of the array data for each Analytic\_Surface type.

error is the return error code for the C and Fortran APIs.

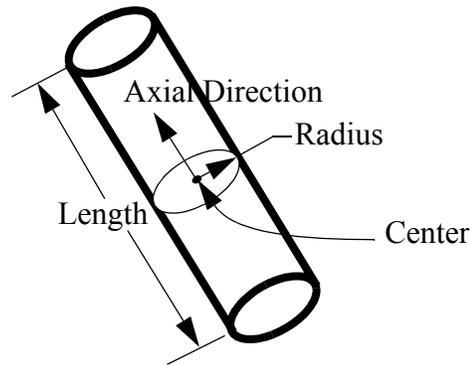


Figure 13 Analytic Cylindrical Surfaces

Table 11 C++ Data Description for Analytic\_Surfaces

	Plane	Sphere	Cylinder_Inside	Cylinder_Outside
as_data[0]	X-Coordinate of Point	X-Coordinate of Center	X-Coordinate of Center	X-Coordinate of Center
as_data[1]	Y-Coordinate of Point	Y-Coordinate of Center	Y-Coordinate of Center	Y-Coordinate of Center
as_data[2]	Z-Coordinate of Point	Z-Coordinate of Center	Z-Coordinate of Center	Z-Coordinate of Center
as_data[3]	X-Component of Normal Vector	Radius	X-Component of Axial Vector	X-Component of Axial Vector
as_data[4]	Y-Component of Normal Vector		Y-Component of Axial Vector	Y-Component of Axial Vector
as_data[5]	Z-Component of Normal Vector		Z-Component of Axial Vector	Z-Component of Axial Vector
as_data[6]			Radius	Radius
as_data[7]			Length	Length

### 3.4.2 Setting the Analytic\_Surface Configuration

The following interface updates the configuration(s) for an Analytic\_Surface.

```

C++      ContactErrorCode
            ContactSearch::Set_Analytic_Surface_Configuration(
                int as_id,
                const double* as_data );

C        FORTRAN(set_analytic_surface_configuration) (
                int* as_id,
                double* as_data,
                int* error );

Fortran  set_analytic_surface_configuration(
                as_id,
                as_data,
                error )

```

where

as\_id is the ACME ID for the Analytic\_Surface.

as\_data is described in Table 11.

error is the return error code for the C and Fortran APIs.

### 3.5 Node\_Block Data

Currently, the only valid type of Node\_Block is NODE. Future releases of ACME will include NODE\_WITH\_SLOPE and NODE\_WITH\_RADIUS.

#### 3.5.1 Setting the Node\_Block Configuration

The following interface allows the host code to specify the configuration(s) for the nodes by Node\_Block. This function can be called at any time but *must* be called prior to the first search. For a one-configuration search, only the current configuration needs to be specified. For two-configuration searches, both current and predicted configurations must be specified. This function should be called every time the nodal positions in the host code are updated. The prototype for this function is:

```

C++      ContactErrorCode
            ContactSearch::Set_Node_Block_Configuration(
                ContactSearch::ContactNode_Configuration
                    config_type,
                int node_block_id,
                const double* positions );

C        FORTRAN(set_node_block_configuration) (
                int* config_type,
                int* node_block_id,
                double* positions,
                int* error );

```

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```
Fortran set_node_block_configuration(  
        config_type,  
        node_block_id,  
        positions,  
        error )
```

where:

config\_type is an enumeration in the C++ API for the configuration:

```
enum ContactSearch::ContactNode_Configuration {  
    CURRENT_CONFIG=1, PREDICTED_CONFIG=2 };
```

node\_block\_id is the ACME ID for the Node\_Block.

positions is an array that holds the nodal positions for every node in the Node\_Block. The data in this array is ordered by x, y and z locations of node 1, followed by x, y and z locations of node 2, etc.

error is the return error code for the C and Fortran APIs.

### 3.5.2 Setting the Node\_Block Kinematic Constraints

The following function informs the ContactSearch object about kinematic constraints for the nodes. If these are specified, the interactions are made consistent with the constraints. Also, the ContactTDEnforcement object computes contact forces that are consistent with these constraints.

```
C++      ContactErrorCode  
ContactSearch::Set_Node_Block_Kinematic_Constraints(  
        int node_block_id,  
        const int* constraints_per_node,  
        const double* constraint_vector );
```

```
C      FORTRAN(set_node_block_kin_cons)(  
        int* node_block_id,  
        int* constraints_per_node,  
        double* constraint_vector,  
        int* error );
```

```
Fortran set_node_block_kin_cons(  
        node_block_id,  
        constraints_per_node,  
        constraint_vector,  
        error )
```

where

node\_block\_id is the ACME ID for this Node\_Block

constraints\_per\_node is how many degrees of freedom are constrained (i.e., 0, 1, 2 or 3).

constraint\_vector is a vector for each node that describes the constraint direction. If constraints\_per\_node is 0 or 3, this vector should be set to 0. If constraints\_per\_node is 1, this vector should be the constrained direction. If constraints\_per\_node is 2, this vector should be the unconstrained direction.

error is the return error code for the C and Fortran APIs.

### 3.5.3 Setting the Node\_Block Attributes

The following function will be used to add Node\_Block attributes, such as the projection direction for all node types, the slope for NODE\_WITH\_SLOPE nodes, or the radius for NODE\_WITH\_RADIUS nodes. Currently, the only attribute supported is the projection direction.

```

C++      ContactErrorCode
            ContactSearch::Set_Node_Block_Attributes (
                ContactSearch::Node_Block_Attribute attribute,
                int node_block_id,
                const double* attributes );

C        FORTRAN(set_node_block_attributes) (
                int* attribute,
                int* node_block_id,
                double* attributes,
                int* error );

Fortran  set_node_block_attributes (
                attribute,
                node_block_id,
                attributes,
                error )

```

where

attribute is an enumeration in the C++ API for the attribute type:

```
enum ContactSearch::Node_Block_Attribute {
    PROJECTION_DIRECTION=0 };
```

node\_block\_id is the ACME ID for this Node\_Block.

attributes is an array of the attribute values for this Node\_Block.

error is the return error code for the C and Fortran APIs.

## 3.6 Face\_Block Data

### 3.6.1 Setting the Face\_Block Attributes

The following function will be used to add Face\_Block attributes. Currently, the only attribute supported is the thickness of shell face types.

```

C++      ContactErrorCode
            ContactSearch::Set_Face_Block_Attributes (
                ContactSearch::Face_Block_Attribute attribute,
                int face_block_id,
                const double* attributes );

C        FORTRAN(set_face_block_attributes) (
                int* attribute,
                int* face_block_id,
                double* attributes,
                int* error );

```

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```
Fortran set_face_block_attributes(  
    attribute,  
    face_block_id,  
    attributes,  
    error )
```

where

attribute is an enumeration in the C++ API for the attribute type:

```
enum ContactSearch::Face_Block_Attribute {  
    SHELL_THICKNESS=1 };
```

face\_block\_id is the ACME ID for this Face\_Block.

attributes is an array of the attribute values for this Face\_Block.

error is the return error code for the C and Fortran APIs.

### 3.7 Table Data

The following function will be used to add a generic table of x-y data pairs. Currently, the only use of tables is in some of the explicit transient dynamic friction models used during enforcement.

```
C++ ContactErrorCode  
ContactSearch::Add_Table(  
    int id,  
    int number_of_points,  
    double* abscissa,  
    double* ordinate );
```

```
C FORTRAN(add_table) (  
    int* id,  
    int* number_of_points,  
    double* abscissa,  
    double* ordinate,  
    int* error );
```

```
Fortran add_table(  
    id,  
    number_of_points,  
    abscissa,  
    ordinate  
    error )
```

where

id is the ACME ID for the table.

number\_of\_points is the number of entries in the table.

abscissa is an array of the x-values for this table.

ordinate is an array of the y-values for this table.

error is the return error code for the C and Fortran APIs.

## 3.8 Search Algorithms

### 3.8.1 Setting the Search Option

By default, both multiple interactions and normal smoothing options are inactive. The following function should be called to activate, deactivate, and control multiple interactions and normal smoothing.

```

C++      ContactErrorCode ContactSearch::Set_Search_Option(
            ContactSearch::Search_Option option,
            ContactSearch::Search_Option_Status status,
            double* data );

C        FORTRAN(set_search_option) (
            int* option,
            int* status,
            double* data,
            int* error );

Fortran  set_search_option(
            option,
            status,
            data,
            error )

```

where

option is an enumeration in the C++ API:

```

enum ContactSearch::Search_Option {
    MULTIPLE_INTERACTIONS=0,
    NORMAL_SMOOTHING=1};

```

status is another enumeration:

```

enum ContactSearch::Search_Option_Status {
    INACTIVE=0,
    ACTIVE=1};

```

data is an array whose first member contains the angle above which the edge between faces is considered to be sharp instead of non-sharp (rounded), and whose second and third members (valid only for the NORMAL\_SMOOTHING option) contain the distance in isoparametric coordinates over which normal smoothing is calculated and the smoothing resolution algorithm, respectively. The integer specifying the smoothing resolution algorithm can take the values USE\_NODE\_NORMAL=0 or USE\_EDGE\_BASED\_NORMAL=1. See the section on Normal Smoothing in the introduction for more information about the smoothing resolution algorithm.

error is the return error code for the C and Fortran APIs.

### 3.8.2 Performing a Static 1-Configuration Search

The following function performs a static 1-configuration search and can be called only after a current configuration has been specified.

```

C++      ContactErrorCode
            ContactSearch::Static_Search_1_Configuration();

```

## Search Functions

```
C          FORTRAN(static_search_1_configuration) (  
                int* error );
```

```
Fortran static_search_1_configuration(  
                error );
```

where

error is the return error code for the C and Fortran APIs.

### 3.8.3 Performing a Static 2-Configuration Search

The following function performs a static 2-configuration search and can be called only if both current and predicted configurations have been specified.

```
C++        ContactErrorCode  
            ContactSearch::Static_Search_2_Configuration();
```

```
C          FORTRAN(static_search_2_configuration) (  
                int* error );
```

```
Fortran static_search_2_configuration(  
                error )
```

where

error is the return error code for the C and Fortran APIs.

### 3.8.4 Performing a Dynamic 2-Configuration Search

The following function performs a dynamic 2-configuration search and can be called only if both the current and predicted configurations have been specified.

```
C++        ContactErrorCode  
            ContactSearch::Dynamic_Search_2_Configuration();
```

```
C          FORTRAN(dynamic_search_2_configuration) (  
                int* error );
```

```
Fortran dynamic_search_2_configuration(  
                error )
```

where

error is the return error code for the C and Fortran APIs.

### 3.8.5 Performing a Dynamic Augmented 2-Configuration Search

The following function performs a dynamic augmented 2-configuration search and can be called only if both the current and predicted configurations have been specified and a ContactTDEnforcement object has been registered with the search.

```

C++      ContactErrorCode
           ContactSearch::Dynamic_Search_Augmented_2_Configuration(
               double* mass,
               double dt_old,
               double dt );

C        FORTRAN(dynamic_search_aug_2_config)(
               double* mass,
               double* dt_old,
               double* dt,
               int* error );

Fortran  dynamic_search_aug_2_config(
               mass,
               dt_old,
               dt,
               error )

```

where

mass is an array that gives the mass of each node.  
dt\_old is the time step for the previous step.  
dt is the time step for the current time step.  
error is the return error code for the C and Fortran APIs.

### 3.9 Interactions

The functions in this section allow the host code to extract the interactions from the ContactSearch object. Typically, the host code should first determine how much memory is needed to hold the interactions before extracting the interactions. *ACME does not currently support the extraction of interactions involving shells.*

#### 3.9.1 Getting the Size of NodeFace\_Interactions

The following function allows the host code to determine how many NodeFace\_Interactions are currently defined in a ContactSearch object and the data size for each interaction.

```

C++      void ContactSearch::Size_NodeFace_Interactions(
               int& number_of_interactions,
               int& nfi_data_size );

C        FORTRAN(size_nodface_interactions)(
               int* number_of_interactions,
               int* nfi_data_size );

Fortran  size_nodface_interactions(
               number_of_interactions,
               nfi_data_size )

```

where

## Search Functions

`number_of_interactions` is the number of active `NodeFace_Interactions` that will be returned by the function `Get_NodeFace_Interactions` (see section 3.9.2).  
`nfi_data_size` is the number of double precision values returned for each interaction.

### 3.9.2 Extracting NodeFace\_Interactions

The following function allows the host code to extract the active `NodeFace_Interactions` from the `ContactSearch` object.

```
C++      void ContactSearch::Get_NodeFace_Interactions (
            int* node_block_ids,
            int* node_indexes_in_block,
            int* node_entity_keys,
            int* face_block_ids,
            int* face_indexes_in_block,
            int* face_procs,
            double* nfi_data );
C        FORTRAN(get_nodface_interactions) (
            int* node_block_ids,
            int* node_indexes_in_block,
            int* node_entity_keys,
            int* face_block_ids,
            int* face_indexes_in_block,
            int* face_procs,
            double* nfi_data );
Fortran  get_nodface_interactions (
            node_block_ids,
            node_indexes_in_block,
            node_entity_keys,
            face_block_ids,
            face_indexes_in_block,
            face_procs,
            nfi_data )
```

where

`node_block_ids` is an array (of length `number_of_interactions`) that contains the `Node_Block` ID for the node in each interaction.

`node_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Node_Block` (using Fortran indexing conventions) for the node in each interaction.

`node_entity_keys` is an array (of length `number_of_interactions`) that contains the node entity key for this interaction.

`face_block_ids` is an array (of length `number_of_interactions`) that contains the `Face_Block` ID for the face in each interaction.

`face_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Face_Block` (using Fortran indexing conventions) for the face in each interaction.

`face_procs` is an array (of length `number_of_interactions`) that contains the processor that owns the face in each interaction.

`nfi_data` is an array (of length `number_of_interactions*nfi_data_size`) that contains the data for each interaction (see Section 1.3.1). The data for each interaction is contiguous (i.e., the first `nfi_data_size` locations contain the data for the first interaction).

### 3.9.3 Getting the Size of NodeSurface\_Interactions

The following function allows the host code to determine how many interactions are currently defined in a ContactSearch object and the data size for each interaction.

```

C++      void ContactSearch::Size_NodeSurface_Interactions (
                int& number_of_interactions,
                int& nsi_data_size );

C        FORTRAN(size_nodesurface_interactions) (
                int* number_of_interactions,
                int* nsi_data_size );

Fortran  size_nodesurface_interactions (
                number_of_interactions,
                nsi_data_size )

```

where

number\_of\_interactions is the number of active NodeSurface\_Interactions that will be returned by the function Get\_NodeSurface\_Interactions (see section 3.9.4).

nsi\_data\_size is the number of double precision values returned for each interaction.

### 3.9.4 Extracting NodeSurface\_Interactions

The following function allows the host code to extract the active NodeSurface\_Interactions from the ContactSearch object.

```

C++      void ContactSearch::Get_NodeSurface_Interactions (
                int* node_block_ids,
                int* node_indexes_in_block,
                int* analyticsurface_ids,
                double* nsi_data );

C        FORTRAN(get_nodesurface_interactions) (
                int* node_block_ids,
                int* node_indexes_in_block,
                int* analyticsurface_ids,
                double* nsi_data );

Fortran  get_nodesurface_interactions (
                node_block_ids,
                node_indexes_in_block,
                analyticsurface_ids,
                nsi_data )

```

where

## Search Functions

`node_block_ids` is an array (of length `number_of_interactions`) that contains the `Node_Block` ID for the node in each interaction.

`node_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Node_Block` (using Fortran indexing conventions) for the node in each interaction.

`analyticsurface_ids` is an array (of length `number_of_interactions`) that contains the ID of the `Analytic_Surface` for each interaction.

`nsi_data` is an array (of length `number_of_interactions*nsi_data_size`) that contains the data for each interaction (see Section 1.3.2). The data for each interaction is contiguous (i.e., the first `nsi_data_size` locations contain the data for the first interaction).

### 3.9.5 Getting the Size of FaceFace\_Interactions

The following function allows the host code to determine how many `FaceFace_Interactions` are currently defined in a `ContactSearch` object and the data size for all interactions.

```
C++      void ContactSearch::Size_FaceFace_Interactions(  
          int& number_of_interactions,  
          int& ffi_data_size );
```

```
C        FORTRAN(size_faceface_interactions) (  
          int* number_of_interactions,  
          int* ffi_data_size );
```

```
Fortran  size_faceface_interactions(  
          number_of_interactions,  
          ffi_data_size )
```

where

`number_of_interactions` is the number of active `FaceFace_Interactions` that will be returned by the function `Get_FaceFace_Interactions` (see section 3.9.6).

`ffi_data_size` is the number of double precision values returned for the entire set of `FaceFace_Interactions`.

### 3.9.6 Extracting FaceFace\_Interactions

The following function allows the host code to extract the active `FaceFace_Interactions` from the `ContactSearch` object.

```
C++      void ContactSearch::Get_FaceFace_Interactions(  
          int* slave_face_block_ids,  
          int* slave_face_indexes_in_block,  
          int* master_face_block_ids,  
          int* master_face_indexes_in_block,  
          int* master_face_procs,  
          int* ffi_index,  
          double* ffi_data );
```

```

C          FORTRAN(get_faceface_interactions) (
                int* slave_face_block_ids,
                int* slave_face_indexes_in_block,
                int* master_face_block_ids,
                int* master_face_indexes_in_block,
                int* master_face_procs,
                int* ffi_index,
                double* ffi_data );

```

```

Fortran  get_faceface_interactions (
                slave_face_block_ids,
                slave_face_indexes_in_block,
                master_face_block_ids,
                master_face_indexes_in_block,
                master_face_procs,
                ffi_index,
                ffi_data)

```

where

slave\_face\_block\_ids is an array (of length number\_of\_interactions) that contains the Face\_Block ID for the slave face in each interaction.

slave\_face\_indexes\_in\_block is an array (of length number\_of\_interactions) that contains the index in the Face\_Block (using Fortran indexing conventions) for the slave face in each interaction.

master\_face\_block\_ids is an array (of length number\_of\_interactions) that contains the Face\_Block ID for the master face in each interaction.

master\_face\_indexes\_in\_block is an array (of length number\_of\_interactions) that contains the index in the Face\_Block (using Fortran indexing conventions) for the master face in each interaction.

master\_face\_procs is an array (of length number\_of\_interactions) that contains the processor that owns the master\_face in each interaction.

ffi\_index is an array (of length number\_of\_interactions) that contains the offset into the ffi\_data array for the data for each interaction (i.e., the data for interaction j begins at ffi\_data[ffi\_index[j]]).

ffi\_data is an array (of length ffi\_data\_size) that contains the data for each interaction (see Section 1.3.3). The data for each interaction is contiguous.

### 3.9.7 Getting the Size of FaceCoverage\_Interactions

The following function allows the host code to determine how many FaceCoverage\_Interactions are currently defined in a ContactSearch object and the data size for all the interactions.

```

C++      void ContactSearch::Size_FaceCoverage_Interactions (
                int& number_of_interactions,
                int& fci_data_size );

```

```

C          FORTRAN(size_facecoverage_interactions) (
                int* number_of_interactions,
                int* fci_data_size );

```

```

Fortran  size_facecoverage_interactions (
                number_of_interactions,

```

## Search Functions

```
fci_data_size )
```

where

`number_of_interactions` is the number of active `FaceCoverage_Interactions` that will be returned by the function `Get_FaceCoverage_Interactions` (see section 3.9.8).

`fci_data_size` is the number of double precision values returned for the entire set of `FaceCoverage_Interactions`.

### 3.9.8 Extracting FaceCoverage\_Interactions

The following function allows the host code to extract the active `FaceCoverage_Interactions` from the `ContactSearch` object.

```
C++    void ContactSearch::Get_FaceCoverage_Interactions (
        int* face_block_ids,
        int* face_indexes_in_block,
        int* fci_index,
        double* fci_data );
```

```
C      FORTRAN(get_facecoverage_interactions) (
        int* face_block_ids,
        int* face_indexes_in_block,
        int* fci_index,
        double* fci_data );
```

```
Fortran get_facecoverage_interactions (
        face_block_ids,
        face_indexes_in_block,
        fci_index,
        fci_data );
```

where

`face_block_ids` is an array (of length `number_of_interactions`) that contains the `Face_Block` ID for the face in each interaction.

`face_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Face_Block` (using Fortran indexing conventions) for the face in each interaction.

`fci_index` is an array (of length `number_of_interactions`) that contains the offset into the `fci_data` array for the data for each interaction (i.e., the data for interaction `j` begins at `fci_data[fci_index[j]]`).

`fci_data` is an array (of length `fci_data_size`) that contains the data for each interaction (see Section 1.3.4). The data for each interaction is contiguous.

### 3.9.9 Getting the Size of ElementElement\_Interactions

The following function allows the host code to determine how many `ElementElement_Interactions` are currently defined in a `ContactSearch` object and the data size for all interactions.

```

C++    void ContactSearch::Size_ElementElement_Interactions(
           int& number_of_interactions,
           int& eei_data_size );

C      FORTRAN(size_elementelement_interactions)(
           int* number_of_interactions,
           int* eei_data_size );

Fortran size_elementelement_interactions(
           number_of_interactions,
           eei_data_size )

```

where

number\_of\_interactions is the number of active ElementElement\_Interactions that will be returned by the function Get\_ElementElement\_Interactions (see section 3.9.10).  
 eei\_data\_size is the number of double precision values returned for the entire set of ElementElement\_Interactions.

### 3.9.10 Extracting ElementElement\_Interactions

The following function allows the host code to extract the active ElementElement\_Interactions from the ContactSearch object.

```

C++    void ContactSearch::Get_ElementElement_Interactions(
           int* slave_element_block_ids,
           int* slave_element_indexes_in_block,
           int* master_element_block_ids,
           int* master_element_indexes_in_block,
           int* master_element_procs,
           int* eei_index,
           double* eei_data );

C      FORTRAN(get_elementelement_interactions)(
           int* slave_element_block_ids,
           int* slave_element_indexes_in_block,
           int* master_element_block_ids,
           int* master_element_indexes_in_block,
           int* master_element_procs,
           int* eei_index,
           double* eei_data );

Fortran get_elementelement_interactions(
           slave_element_block_ids,
           slave_element_indexes_in_block,
           master_element_block_ids,
           master_element_indexes_in_block,
           master_element_procs,
           eei_index,
           eei_data)

```

where

`slave_element_block_ids` is an array (of length `number_of_interactions`) that contains the `Element_Block` ID for the slave element in each interaction.

`slave_element_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Element_Block` (using Fortran indexing conventions) for the slave element in each interaction.

`master_element_block_ids` is an array (of length `number_of_interactions`) that contains the `Element_Block` ID for the master element in each interaction.

`master_element_indexes_in_block` is an array (of length `number_of_interactions`) that contains the index in the `Element_Block` (using Fortran indexing conventions) for the master element in each interaction.

`master_element_procs` is an array (of length `number_of_interactions`) that contains the processor that owns the master element in each interaction.

`eei_index` is an array (of length `number_of_interactions`) that contains the offset into the `eei_data` array for the data for each interaction (i.e., the data for interaction `j` begins at `eei_data[eei_index[j]]`).

`eei_data` is an array (of length `eei_data_size`) that contains the data for each interaction (see Section 1.3.3). The data for each interaction is contiguous.

### 3.9.11 Deleting Interactions

The following function permits the host code to delete all previously found interactions before conducting a new search. This function is of particular use when a single search object conducts two different enforcements. For example, if an analysis uses both `ContactGapRemoval` and `ContactTDEnforcement` with a single `ContactSearch` object, then the interactions used for `ContactGapRemoval` can negatively affect the `ContactTDEnforcement`. In this case, it is better to delete the interactions determined for `ContactGapRemoval` before doing a search for `ContactTDEnforcement`.

```
C++      ContactErrorCode  
          ContactSearch::Delete_All_Interactions();
```

```
C        FORTRAN(delete_all_interactions)();
```

```
Fortran  delete_all_interactions()
```

## 4. Gap Removal Enforcement Functions

The gap removal enforcement will compute a displacement increment needed to remove overlaps, as discussed in Section 1.6. This section describes functions that construct and operate on `ContactGapRemoval` “objects.” For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. In the C and Fortran APIs, these functions create and operate on a `ContactGapRemoval` “object,” only one of which is currently allowed.

In each section delineating the ACME API functions (Sections 2, 3, 4, 5, and 6), the different forms for the C++, C, and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. On the other hand, the C and Fortran APIs, which in actuality have been combined into a single interface, are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address, not by value. For Fortran, there exists no capability to pass data by value, so simply specifying the name of the variable or array will allow it to be passed appropriately.

The `Enforcement_Interface.h` header file, located in the ACME enforcement directory, includes the prototypes for the C and Fortran functions described in this chapter, and the `ContactGapRemoval.h` file includes the C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in `ContactEnforcement.h` and `ContactGapRemoval.h`; these indicate the acceptable integral values that may be used in the C and Fortran APIs.

ACME does not currently support gap removal enforcement for analyses which include shell faces (`SHELLQUADFACEL4` and `SHELLTRIFACEL3`).

### 4.1 Constructing a `ContactGapRemoval` Object

There is one general purpose constructor for the `ContactGapRemoval` object. There are two restart constructors for this object. They are of the same form as all the other objects, as discussed in Sections 1.9, 2.3, and 2.4, so they will not be discussed further in this section.

The prototype for the initial `ContactGapRemoval` constructor is:

```

C++      ContactGapRemoval::ContactGapRemoval (
            double* Enforcement_Data,
            ContactSearch* search,
            ContactSearch::ContactErrorCode& error );

C        FORTRAN(build_gap_removal) (
            double* Enforcement_Data,
            int* error );

Fortran  build_gap_removal (

```

## Gap Removal Enforcement Functions

```
Enforcement_Data,  
error );
```

where

Enforcement\_Data is a real array (of length  $1 * (\text{number of entity keys}) * (\text{number of entity keys})$ ) that stores the kinematic partition factor. It is structured  $[\text{n\_key} * \text{number\_entity\_keys} + \text{f\_key}]$  where n\_key is the node key and f\_key is the face key. The kinematic partition factor controls the master/slave relationship between two entities as described in Section 1.5.

search is the ContactSearch object from which the topology, interactions, and configurations are obtained.

error is the error code (described in Section 1.7) that will reflect any errors that were detected.

### 4.2 Computing the Gap Removal Displacements

This member function computes the displacement increments necessary to remove any initial gaps that are contained in the ContactSearch object topology. A static 1-configuration search should be used to define the interactions prior to calling this member function (regardless of the type of mechanics being solved).

```
C++      ContactErrorCode ContactGapRemoval::Compute_Gap_Removal(  
          double* displ_cor);  
  
C        FORTRAN(compute_gap_removal)(  
          double* displ_cor,  
          int* error );  
  
Fortran  compute_gap_removal(  
          displ_cor,  
          error )
```

where

displ\_cor is the displacement correction needed at each node to remove the initial gaps.

### 4.3 Destroying a ContactGapRemoval Object

```
C++      ~ContactGapRemoval();  
  
C        FORTRAN(cleanup_gap_removal)();  
  
Fortran  cleanup_gap_removal()
```

## 5. Explicit Transient Dynamic Enforcement Functions

This section describes functions that construct and operate on `ContactTDEnforcement` “objects.” For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. In the C and Fortran APIs, these functions create and operate on a `ContactTDEnforcement` “object,” only one of which is currently allowed.

In each section delineating the ACME API functions (Sections 2, 3, 4, 5, and 6), the different forms for the C++, C, and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. On the other hand, the C and Fortran APIs, which in actuality have been combined into a single interface, are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address, not by value. For Fortran, there exists no capability to pass data by value, so simply specifying the name of the variable or array will allow it to be passed appropriately.

The `Enforcement_Interface.h` header file, located in the ACME enforcement directory, includes the prototypes for the C and Fortran functions described in this chapter, and the `ContactTDEnforcement.h` file includes the C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in `ContactEnforcement.h` and `ContactTDEnforcement.h`; these indicate the acceptable integral values that may be used in the C and Fortran APIs.

### 5.1 Creating a `ContactTDEnforcement` Object

There is one general purpose constructor for the `ContactTDEnforcement` object. There are two restart constructors for this object. They are of the same form as all the other objects, as discussed in Sections 1.9, 2.3, and 2.4, so they will not be discussed further in this section.

The prototype for the initial `ContactTDEnforcement` constructor is:

```

C++      ContactTDEnforcement::ContactTDEnforcement (
            const double* Enforcement_Data,
            ContactSearch* search,
            ContactSearch::ContactErrorCode& error);

C        FORTRAN(build_td_enforcement) (
            double* Enforcement_Data,
            int* error);

Fortran  build_td_enforcement (
            Enforcement_Data,
            error)

```

where

## Explicit Transient Dynamic Enforcement Functions

Enforcement\_Data is a real array (of length  $2*(\text{number of entity keys})*(\text{number of entity keys})$ ) that stores the kinematic partition factor and the friction model id. It is structured  $[(n\_key*\text{number\_entity\_keys}+f\_key)*\text{size\_data\_per\_pair}+\text{variable\_index}]$  where  $n\_key$  is the node key and  $f\_key$  is the face key. The kinematic partition factor controls the master/slave relationship between two entities. A factor between 0 and 1 specifies a fixed kinematic partitioning. A value of 2 indicates the code should compute this for each interaction pair based on the physical data. The friction model id pertains to the constitutive behavior of the interactions and is described in the following section.

search is the ContactSearch object from which the topology, interactions, and configurations are obtained.

error is the error code (described in Section 1.7) that will reflect any errors that were detected.

### 5.2 Defining Enforcement Models

The contact behavior is controlled by enforcement models. Six types of enforcement models are currently supported; TD\_FRICTIONLESS, TD\_CONSTANT\_FRICTION, TD\_TIED, TD\_SPOT\_WELD, TD\_PRESSURE\_DEPENDENT and TD\_VELOCITY\_DEPENDENT, TD\_POINT\_WELD, TD\_ADHESION, TD\_COHESIVE\_ZONE. For the C++ API, please note that Add\_Enforcement\_Model is a function inherited by ContactTDEnforcement. To define the enforcement model to be used, the following function must be called:

```
C++      ContactSearch::ContactErrorCode
           ContactEnforcement::Add_Enforcement_Model (
               Enforcement_Model_Types type,
               int* ID,
               int* integer_data,
               double* real_data);
```

```
C        FORTRAN(td_add_enf_model) (
           int* type,
           int* id,
           int* integer_data,
           double* real_data,
           int* error);
```

```
Fortran  td_add_enf_model (
           type,
           id,
           integer_data,
           real_data,
           error)
```

where

type is the enforcement model type (as shown in Table 12).

id is a positive integer identifier for the model.

integer\_data is an array of integer data that is particular to the model (as shown in Table 12).

real\_data is an array of real data that is particular to the model (as shown in Table 12).

error is the return error code for the C and Fortran APIs.

Table 12 Transient Dynamic Enforcement Models and Data

Type	Integer Data	Real Data
TD_FRICTIONLESS = 1	None	None
TD_CONSTANT_FRICTION=2	None	Friction Coefficient
TD_TIED=3	None	None
TD_SPOT_WELD=4	Failure_Steps Failed_Model_ID	Normal Capacity Tangential Capacity
TD_PRESSURE_DEPENDENT=5	None	Friction Coefficient Reference Pressure Offset Pressure Pressure Exponent
TD_VELOCITY_DEPENDENT=6	None	Static Coefficient Dynamic Coefficient Velocity Decay
TD_POINT_WELD=7	Normal_Traction_ Function_ID Tangential_Functi on_Table_ID Failure_Steps Failed_Model_ID	Failure_Criterion_Exponen t
TD_ADHESION=8	Adhesion_Functio n_ID	None
TD_COHESIVE_ZONE=9	Traction_Displace ment_Function_ID	Critical_Normal_Gap Critical_Tangential_Gap

Notes: NodeSurface\_Interactions currently cannot use the TD\_TIED and TD\_SPOT\_WELD model types.

For the TD\_FRICTIONLESS model, only compressive normal tractions are allowed to enforce impenetrability.

The TD\_CONSTANT\_FRICTION model is a Coulomb model with the tangential traction limit given by  $\mu p$ , where  $\mu$  is the Friction Coefficient and  $p$  is the normal pressure.

No relative motion is allowed for the TD\_TIED model.

For the TD\_SPOT\_WELD model, the behavior is the same as the TD\_TIED model until a failure limit based on Normal and Tangential Capacity is reached. At this point, the model

## Explicit Transient Dynamic Enforcement Functions

takes the requested number of Failure Steps to transition to the Failed Model prescribed by the Failed\_Model\_ID.

The TD\_PRESSURE\_DEPENDENT model is similar to the TD\_CONSTANT\_FRICTION model, except the tangential limit is given by  $\mu \left( \frac{p + p_o}{p_r} \right)^k$ , where  $p_o$  is the Offset Pressure,  $p_r$  is the Reference Pressure and  $k$  is the Pressure Exponent.

The TD\_VELOCITY\_DEPENDENT model is also similar to the TD\_CONSTANT\_FRICTION model, except here the tangential limit is given by  $(\mu_s - \mu_d) \exp(-d\|v\|) + \mu_d$ , where  $\mu_s$  is the Static Coefficient,  $\mu_d$  is the Dynamic Coefficient,  $d$  is the Velocity Decay and  $\|v\|$  is the magnitude of the (tangential) relative velocity.

The TD\_POINT\_WELD model is similar to the TD\_SPOT\_WELD model, except that in the pre-failure regime, the interactions follow the force-displacement relations given by the two tables Normal\_Traction\_Function (only in tension) and Tangential\_Traction\_Function. The values of ordered pairs in these tables are expected to be non-negative and the last ordinates are used as critical force values for the failure criterion (i.e. they can not be zero).

The TD\_ADHESION model is an enhanced version of TD\_FRICTIONLESS, where, in tension, a restoring force is given by the tabular Adhesion\_Function. The values of the Adhesion\_Function are expected to be non-negative.

The TD\_COHESIVE\_ZONE model follows Tvergaard and Hutchinson's (1993) developments, where the normal and tangential cohesive tractions are coupled through a quadratic failure variable. This variable is the only argument to a single (tabular) force-displacement relation which is scaled by Critical\_Normal\_Gap and Critical\_Tangential\_Gap to obtain the tensile normal force and tangential force, respectively. In compression the normal force sufficient to prevent penetration is used. Also, since the failure variable is non-negative any part of the tabular force-displacement curve with negative abscissas is ignored.

For all the models with adhesive/cohesive behavior (TD\_ADHESION, TD\_COHESIVE\_ZONE), the Search\_Normal\_Tolerance should be set to be exactly equal to the Critical\_Normal\_Gap (in the case of TD\_ADHESION, this is the last abscissa of the Adhesion\_Function table).

All models are currently force-based, i.e. they do not scale appropriately with changing element size. For a given element size, analysts can correct for this by scaling the input values of, say, the Traction\_Displacement\_Function of the TD\_COHESIVE\_ZONE model. This will be corrected in future releases.

### 5.3 Controlling the Algorithm

The enforcement algorithms are iterative in nature (i.e., a predictor-corrector algorithm is used). The accuracy of the algorithm can be improved by doing additional iterations. Initial testing indicates that 5 iterations dramatically improve the accuracy of the solution (especially for frictional problems). If there is a mesh mismatch and the automatic kinematic partitioning is used, more iterations may be necessary. The following member function allows the user to set the number of iterations to use (the default is 1 if it is not explicitly set).

```

C++      ContactSearch::ContactErrorCode
           ContactTDEnforcement::Set_Number_of_Iterations (
               int number_iterations);

C        FORTRAN(set_td_iterations) (
               int* number_iterations,
               int* error);

Fortran  set_td_iterations (
               number_iterations,
               error);

```

where

number\_iterations is the number of iterations to use in the enforcement.  
 error is the return error code for the C and Fortran APIs.

### 5.4 Specifying Symmetric Nodes

This enforcement was originally written for Lagrangian based contact. Its use has expanded to a number of codes and algorithms including ALEGRA/SHISM which is a coupled Lagrangian/ALE technique for modeling penetration events (e.g., earth penetrators, armor, etc.). Due to the formulation of this problem, the tip of the penetrator must be treated in a different manner than a typical contact. Specifically, the tip node of the penetrator and the corresponding node of the ALE mesh must have consistent constraints. The search does not give the symmetric interactions in general. The ability to enforce this symmetry is provided with the following function. This should ONLY be used with the ALEGRA/SHISM capability.

```

C++      ContactSearch::ContactErrorCode
           ContactTDEnforcement::Enforce_Symmetry_on_Nodes (
               int exodus_id_1,
               int exodus_id_2 );

C        FORTRAN(set_td_enf_symm_nodes) (
               int* exodus_id_1,
               int* exodus_id_2,
               int* error );

FORTTRAN set_td_enf_symm_nodes (

```

## Explicit Transient Dynamic Enforcement Functions

```
exodus_id_1,  
exodus_id_2,  
error );
```

where

exodus\_id\_1 is the exodus id of the tip node of the penetrator.  
exodus\_id\_2 is the exodus id of the corresponding node on the ALE target mesh.  
error is the return error code for the C and Fortran APIs.

### 5.5 Computing the Contact Forces

The following member function computes the contact forces necessary to enforce the contact constraints that are contained in the ContactSearch object.

```
C++ ContactSearch::ContactErrorCode  
ContactTDEnforcement::Compute_Contact_Force(  
    double dt_old,  
    double dt,  
    double* mass,  
    double* density,  
    double* wavespeed,  
    double* force);  
  
C FORTRAN(compute_td_contact_force) (  
    double* dt_old,  
    double* dt,  
    double* mass,  
    double* density,  
    double* wavespeed,  
    double* force,  
    int* error);  
  
Fortran compute_td_contact_force(  
    dt_old,  
    dt,  
    mass,  
    density,  
    wavespeed,  
    force,  
    error)
```

where

dt\_old is the previous time step for a central difference integrator.  
dt is the current time step for a central difference integrator.  
mass is an array that contains the nodal mass for each node.  
density an array that contains the nodal “density”. Computing this as the nodal mass divided by the sum of the contributing element volumes works well. This array is used in computing the automatic kinematic partitioning.

wavespeed is an array that contains the nodal “wavespeed”. Computing this as the average of the contributing element wavespeeds works well. This array is used in computing the automatic kinematic partitioning.

force is the return array containing the computed contact force vectors for each node.

error is the return error code for the C and Fortran APIs.

## 5.6 Extracting Plot Variables

The ContactTDEnforcement includes support for extracting variables that can be useful for plotting. The variables that can be extracted are listed in Table 13.

Table 13 TD Plot Variables

Plot Variable	Description
CONFACE = 1	The value of CONFACE denotes status of interactions at a node. A value of 0.5 indicates the node is not in contact. A value of 1, 2, or 3 denotes the number of interactions at that node.
NORMAL_FORCE_MAG = 2	This variable holds the normal force magnitude for the node. If multiple constraints exist at a node, this value is for the last constraint.
TANGENTIAL_FORCE_MAG = 3	This variable holds the tangential force magnitude for the node. If multiple constraints exist at this node, the value is for the last constraint.
CDIRNOR[XYZ] = [4,5,6]	The vector components of the normal direction for the constraint at a node are held in CDIRNOR. If multiple constraints exist at a node, these values are for the last constraint.
CDIRTAN[XYZ] = [7,8,9]	The vector components of the tangential direction for the constraint at a node are held in CDIRTAN. If multiple constraints exist at a node, these values are for the last constraint.

Table 13 TD Plot Variables

Plot Variable	Description
SLIPMAG = 10	SLIPMAG is the incremental slip for this time step at a node. If multiple constraints exist at a node, this value is for the last constraint

The interface for getting these variables is:

```

C++      ContatSearch::ContactErrorCode
            ContactTDEnforcement::Get_Plot_Variable(
                Contact_TDEnf_Plot_Vars plot_var,
                Real* data);

C        FORTRAN(get_td_plot_variable) (
                int& plot_var,
                Real* data,
                int& error);

Fortran  get_td_plot_variable(
                plot_var,
                data,
                error)

```

where

plot\_var is the value for the variable given in Table 13.  
data is an array (number of nodes long) in which the values will be loaded.  
error is the return error code.

## 5.7 Destroying a ContactTDEnforcement Object

```

C++      ~ContactTDEnforcement ();

C        FORTRAN(cleanup_td_enforcement) ();

Fortran  cleanup_td_enforcement ()

```

## 6. Tied Kinematics Enforcement Functions

The `ContactTiedKinematics` object will compute positions for nodes to satisfy a no-relative-motion requirement (limited to a pure master-slave relationship) as discussed in Section 1.7. For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. In the C and Fortran APIs, these functions create and operate on a `ContactTiedKinematics` “object,” only one of which is currently allowed.

In each section delineating the ACME API functions (Sections 2, 3, 4, 5, and 6), the different forms for the C++, C, and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. On the other hand, the C and Fortran APIs, which in actuality have been combined into a single interface, are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address, not by value. For Fortran, there exists no capability to pass data by value, so simply specifying the name of the variable or array will allow it to be passed appropriately.

The `Enforcement_Interface.h` header file, located in the ACME enforcement directory, includes the prototypes for the C and Fortran functions described in this chapter, and the `ContactTiedKinematics.h` file includes the C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in `ContactEnforcement.h` and `ContactTiedKinematics.h`; these indicate the acceptable integral values that may be used in the C and Fortran APIs.

Currently, a tied interaction between the edge of a shell and another face is enforced as a pinned connection, i.e. the relative motion of the nodes on the shell edge do not move, but the shell is free to rotate about the edge.

### 6.1 Constructing a `ContactTiedKinematics` Object

There is one general purpose constructor for the `ContactTiedKinematics` object. There are two restart constructors for this object. They are of the same form as all the other objects, as discussed in Sections 1.9, 2.3, and 2.4, so they will not be discussed further in this section.

The prototype for the initial `ContactTiedKinematics` constructor is:

```

C++      ContactTiedKinematics::ContactTiedKinematics (
            double* Enforcement_Data,
            ContactSearch* search,
            ContactSearch::ContactErrorCode& error );

C        FORTRAN(build_tied_kinematics) (
            double* Enforcement_Data,
            int* error );

```

## Tied Kinematics Enforcement Functions

```
Fortran build_tied_kinematics(  
    Enforcement_Data,  
    error );
```

where

Enforcement\_Data is a real array (of length  $1 * (\text{number of entity keys}) * (\text{number of entity keys})$ ) that stores the kinematic partition factor. It is structured  $[\text{n\_key} * \text{number\_entity\_keys} + \text{f\_key}]$  where n\_key is the node key and f\_key is the face key. The kinematic partition factor controls the master/slave relationship between two entities as described in Section 1.5. For this object the kinematic partition MUST specify a pure master/slave relationship.

search is the ContactSearch object from which the topology, interactions, and configurations are obtained.

error is the error code (described in Section 1.7) that will reflect any errors that were detected.

### 6.2 Computing the ContactTiedKinematic Displacements

A static 1-configuration search should be used to define the interactions prior to calling this member function. This function computes the final position of all nodes so that they kinematically satisfy the tied constraints.

```
C++    ContactErrorCode  
        ContactTiedKinematics::Compute_Position(  
            double* position);
```

```
C      FORTRAN(compute_tied_position)(  
            double* position,  
            int* error );
```

```
Fortran compute_tied_position(  
    position,  
    error )
```

where

position is an array of positions ordered (x,y,z) for node 1, (x,y,z) for node 2, etc. On input this is the current positions of all nodes. On output it is the positions of all the nodes that satisfy the no-relative-motion requirement between the slave nodes and the master surface face.

### 6.3 Destroying a ContactTiedKinematics Object

```
C++    ~ContactTiedKinematics();
```

```
C      FORTRAN(cleanup_tied_kinematics)();
```

```
Fortran cleanup_tied_kinematics()
```

## 7. Volume Transfer

This section describes functions that construct and operate on `ContactVolumeTransfer` “objects.” For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. In the C and Fortran APIs, these functions create and operate on a `ContactVolumeTransfer` “object,” only one of which is currently allowed.

In each section delineating the ACME API functions, the different forms of the C++, C and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. The C and Fortran APIs are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address and not value. For Fortran, it is not possible to pass by value, so simply specifying the name of the variable or array is sufficient.

The `Enforcement_Interface.h` header file, located in the ACME enforcement directory, includes the prototypes for the C and Fortran functions described in this chapter, and the `ContactVolumeTransfer.h` file includes the C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in `ContactEnforcement.h` and `ContactVolumeTransfer.h`; these indicate the acceptable integer values for the C and Fortran APIs.

### 7.1 Constructing a Volume TransferObject

There is one general purpose constructor for the `ContactVolumeTransfer` object. There are two restart constructors for this object. They are of the same form as all the other objects, as discussed in Sections 2.3 and 2.4, so they will not be discussed further in this section.

The prototype for the initial `ContactVolumeTransfer` constructor is:

```

C++      ContactVolumeTransfer::ContactVolumeTransfer (
                const double* Enforcement_Data,
                ContactSearch* search,
                ContactSearch::ContactErrorCode& error );

C        FORTRAN(build_vol_tran) (
                double* Enforcement_Data,
                int* error );

Fortran  build_vol_tran (
                Enforcement_Data,
                error )

```

where,

`Enforcement_Data` is a real array. This array is currently unused and any data passed to the object is ignored.

`search` is the `ContactSearch` object from which the topology, interactions, and configurations are obtained.

error is the error code (described in Section 1.7) that will reflect any errors that were detected.

## 7.2 Computing the Transferred Element and Nodal Data

The following member function performs the transfer of element and nodal data from the master to slave mesh. Nodal variable data is interpolated from the master (donor) to slave (receiver) mesh using linear interpolation. Element variable data is mapped between the two meshes using volume fraction weighting with the result being divided by the volume fraction of the receiving mesh filled by the donor mesh (volume\_fraction below). Output includes both the transferred nodal and element variables and the volume fraction of the receiving mesh filled by the donor mesh.

```

C++      ContactSearch::ContactErrorCode
            ContactVolumeTransfer::Compute_Volume_Transfer(
                int num_node_vars,
                int num_elem_vars,
                const double* donor_node_vars,
                const double* donor_elem_vars,
                double* receiver_node_vars,
                double* receiver_elem_vars,
                double* volume_fraction );

C        FORTRAN(compute_vol_tran)(
                int num_node_vars,
                int num_elem_vars,
                double* donor_node_vars,
                double* donor_elem_vars,
                double* receiver_node_vars,
                double* receiver_elem_vars,
                double* volume_fraction,
                int* error);

Fortran  compute_vol_tran(
                num_node_vars,
                num_elem_vars,
                donor_node_vars,
                donor_elem_vars,
                receiver_node_vars,
                receiver_elem_vars,
                volume_fraction,
                error )

```

where

num\_node\_vars is the number of nodal variables to be transferred.

num\_elem\_vars is the number of element variables to be transferred.

donor\_node\_vars is an array that contains the nodal variables to be transferred at each node and so is num\_node\_vars\*number\_of\_nodes long. The array is structured such that variables cycle faster than nodes.

donor\_elem\_vars is an array that contains the element variables to be transferred at each node and so is num\_elem\_vars\*number\_of\_elems long. The element variables cycle faster than do the elements.

receiver\_node\_vars is an array which is initially empty and is filled with the transferred nodal data.

The array is num\_node\_vars\*number\_of\_nodes long and nodal variables cycle faster than do the nodes.

receiver\_elem\_vars is an array which is initially empty and is filled with the transferred element data. The array is num\_node\_vars\*number\_of\_elements long and nodal variables cycle faster than do the nodes.

volume\_fraction is an array number\_of\_elements long which, upon exit, contains the volume fraction of the receiver elements filled by the donor elements.

### 7.3 Destroying a ContactVolumeTransfer Object

**C++**        ~ContactVolumeTransfer ();

**C**            FORTRAN(cleanup\_vol\_tran) ();

**Fortran**    cleanup\_vol\_tran ()



## 8. MPC Enforcement

This section describes functions that construct and operate on ContactMPCs “objects.” For the C++ API, these are true objects permitted by the object-oriented capabilities of the language. In the C and Fortran APIs, these functions create and operate on a ContactMPCs “object,” only one of which is currently allowed.

In each section delineating the ACME API functions, the different forms of the C++, C and Fortran syntax are presented together for each function call. The C++ API uses the full object-oriented capabilities of the language. The C and Fortran APIs are a collection of functions that have a pure C interface and can be called from either C or Fortran routines. The FORTRAN macro that surrounds all calls in the C syntax converts the function by appending an underscore to the end of the function name, if appropriate. Because of this, all data in the C API must be passed by address and not value. For Fortran, it is not possible to pass by value, so simply specifying the name of the variable or array is sufficient.

The Enforcement\_Interface.h header file, located in the ACME enforcement directory, includes the prototypes for the C and Fortran functions described in this chapter, and the ContactMPCs.h file includes the C++ prototypes. Enumerations for symbolic types used in the C++ API are also found in ContactEnforcement.h and ContactMPCs.h; these indicate the acceptable integer values for the C and Fortran APIs.

### 8.1 Constructing a ContactMPCs Object

There is one general purpose constructor for the ContactMPCs object. There are two restart constructors for this object. They are of the same form as all the other objects, as discussed in Sections 2.3 and 2.4, so they will not be discussed further in this section.

The prototype for the initial ContactMPCs constructor is:

```

C++      ContactMPCs::ContactMPCs (
                const double* Enforcement_Data,
                ContactSearch* search,
                ContactSearch::ContactErrorCode& error );

C        FORTRAN(build_mpc_eqns) (
                double* Enforcement_Data,
                int* error );

Fortran  build_mpc_eqns (
                Enforcement_Data,
                error )

```

where,

Enforcement\_Data is a real array. This array is currently unused and any data passed to the object is ignored.

search is the ContactSearch object from which the topology, interactions, and configurations are obtained.

error is the error code (described in Section 1.7) that will reflect any errors that were detected.

## 8.2 Computing the Multiple Point Constraint (MPC) Equations

The following member function calculates the MPC equations when called. No output (other than an error code) is returned.

```

C++      ContactSearch::ContactErrorCode
            ContactMPCs::Compute_MPCs (
                Id_Numbering_Scheme id_num_scheme);

C        FORTRAN(compute_mpc_eqns) (
                int& id_num_scheme,
                int* error);

Fortran  compute_mpc_eqns (
                id_num_scheme,
                error )

```

where

id\_num\_scheme is the numbering scheme to be used when returning face and node ids. Choices are HOST\_GLOBAL\_ID (= 1) or ACME\_LOCAL\_ID (= 2). When HOST\_GLOBAL\_ID is chosen, face and node IDs are numbered as the face\_global\_ids and node\_global\_ids supplied by the host code when the ContactSearch object was created (see Section 3.1). When ACME\_LOCAL\_ID is selected, face and node IDs are returned as the local and owning processor ID pairs.

error is the return error code for the C and Fortran APIs.

## 8.3 Getting the Number of MPC Equations

The following member function returns the number of MPC equations. This function must be called after the Compute function of Section 8.2. This function returns the number of MPC equations.

```

C++      ContactSearch::ContactErrorCode
            ContactMPCs::Number_of_MPC_Equations (
                int& number_of_equations);

C        FORTRAN(get_num_mpceqns) (
                int& number_of_equations,
                int* error);

Fortran  get_num_mpceqns (
                number_of_equations,
                error )

```

where

number\_of\_equations is the number of MPC equations.  
error is the return error code for the C and Fortran APIs.

## 8.4 Getting the MPC Equations

The following member function returns the Multiple Point Constraint equations in terms of the involved slave-nodes, master-faces, master-face nodes and associated constraint coefficients. This function must be called after getting the number of constraint equations through a call to the function of Section 8.3.

```

C++      ContactSearch::ContactErrorCode
            ContactMPCs::Get_MPC_Equations(
                int number_of_equations,
                int* snode_pid,
                int* snode_lid,
                int* mface_pid,
                int* mface_lid,
                int* nface_nodes,
                int* fnode_pid,
                int* fnode_lid,
                double* fnode_coefs);

C        FORTRAN(get_num_mpceqns) (
                int& number_of_equations,
                int* error);

Fortran  get_num_mpceqns (
                number_of_equations,
                error )

```

where

`number_of_equations` is the number of MPC equations.  
`snode_pid` is an array (`number_of_equations` long) containing the most significant word of the slave node ID for each MPC equation. Either processor ID (`ACME_LOCAL_ID`) or the most significant word in the host code global node ID (`HOST_GLOBAL_ID`) is returned.  
`snode_lid` is an array (`number_of_equations` long) containing the least significant word of the slave node ID for each MPC equation. Either local id (`ACME_LOCAL_ID`) or the least significant word in the host code global node id (`HOST_GLOBAL_ID`) is returned.  
`mface_pid` is an array (`number_of_equations` long) containing the most significant word of the master face ID for each MPC equation. Either processor ID (`ACME_LOCAL_ID`) or the most significant word in the host code global face ID (`HOST_GLOBAL_ID`) is returned.  
`mface_lid` is an array (`number_of_equations` long) containing the least significant word of the slave node ID for each MPC equation. Either local ID (`ACME_LOCAL_ID`) or the least significant word in the host code global face ID (`HOST_GLOBAL_ID`) is returned.  
`nface_nodes` is an array (`number_of_equations` long) containing the number of nodes attached to the master face for this MPC equation.  
`fnode_pid` is an array (`8*number_of_equations` long) containing the most significant word of the master face node ID for each MPC equation. Either processor ID (`ACME_LOCAL_ID`) or the most significant word in the host code global node ID (`HOST_GLOBAL_ID`) is returned. If the master face has fewer than 8 nodes, the remaining IDs are returned as zero.  
`fnode_lid` is an array (`8*number_of_equations` long) containing the least significant word of the master face node ID for each MPC equation. Either local id (`ACME_LOCAL_ID`) or the least significant word in the host code global node id (`HOST_GLOBAL_ID`) is returned. If the master face has fewer than 8 nodes, the remaining IDs are returned as zero.

## MPC Enforcement

`fnode_coefs` is an array ( $8 \times \text{number\_of\_equations}$  long) containing the coefficients for the MPC equation. The coefficients,  $C_I$ , are written such that the MPC equation is given by  $1 + C_1 + C_2 + \dots = 0$ . If the master face has fewer than 8 nodes, the remaining coefficients are returned as zero.

`error` is the return error code for the C and Fortran APIs.

### 8.5 Destroying a ContactVolumeTransfer Object

**C++**      `~ContactMPCs ();`

**C**        `FORTRAN (cleanup_mpc_eqns) ();`

**Fortran** `cleanup_mpc_eqns ()`

## 9. Example

This section outlines a simple single-processor search example with multiple face types and an Analytic\_Surface using the C++ interface. The only differences in using the C or Fortran interface would be calling the analogous C/Fortran functions (the data and calling sequence would be the same).

### 9.1 Problem Description

Consider the problem shown in Figure 14, where two bodies impact each other as well as an analytic plane. One body is discretized with 8-node hexahedral elements and the other is discretized with 4-node tetrahedral elements (the discretizations are not shown in Figure 14, however). For this example, we consider a dynamic search for NodeFace\_Interactions. As previously noted, all interactions with Analytic\_Surfaces are static checks, regardless of the type of search, for this version of ACME. The host code is responsible for creating a topological representation of the surface to supply to ACME. The Face\_Block numbering is shown in Figure 15, the surface topology is shown in Figure 16, and the connectivities for the faces are given in Table 14.

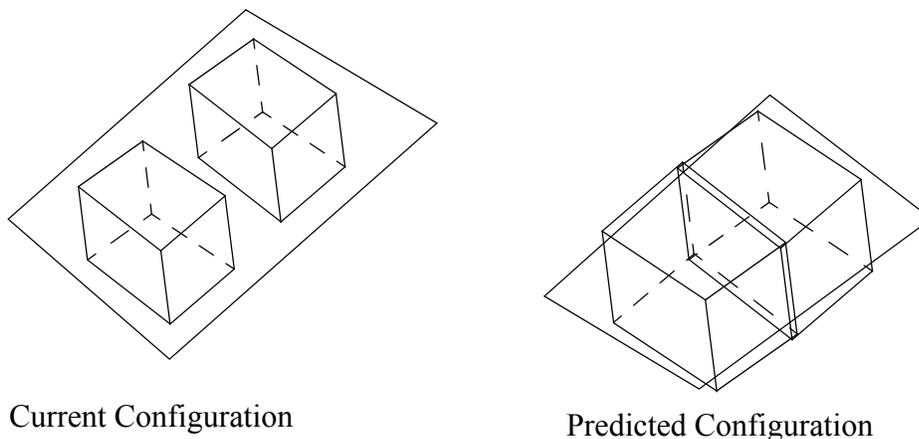


Figure 14 Example impact problem (two rectangular bodies and an Analytic\_Surface)

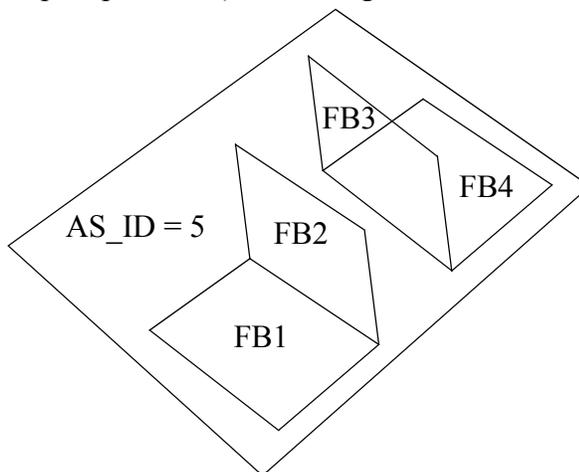


Figure 15 Face\_Block Numbering for Example Problem

## Example

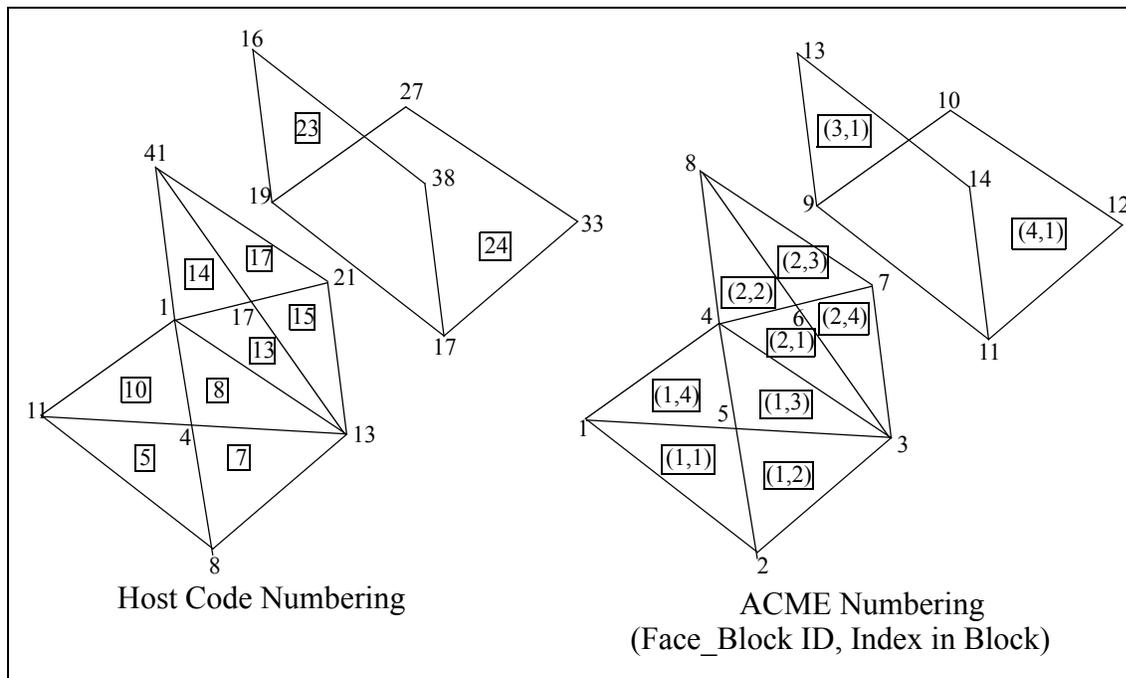


Figure 16 Surface Topology for Example Problem

Because all of the nodes are attached to faces, only one Node\_Block is used (this block will then have an ID of 1). For the Exodus IDs, we will simply use the local ID. For the global IDs (which are two integers), we will use (0,local\_id). For this example, consider the case where the user wants to specify one set of search tolerance values between the two bodies and another set between each body and the analytic plane, as well as specifying the interaction type between each. To accommodate this, the number of Face\_Blocks will be four (one for the “side” face of the left body, one for the “bottom” face of the left body, one for the “side” face of the right body and one for the “bottom” face of the right body). The total number of Entity\_Keys will then be 5 (one each for the Face\_Blocks and an additional one for the PLANE Analytic\_Surface).

Table 14 Face\_Blocks for Example Problem

Host Code Face ID	Face_Block ID	Index in Block	Connectivity
5	1	1	1-5-2
7	1	2	2-5-3
8	1	3	3-5-4
10	1	4	5-1-4

Table 14 Face\_Blocks for Example Problem

Host Code Face ID	Face_Block ID	Index in Block	Connectivity
13	2	1	4-6-3
14	2	2	4-8-6
17	2	3	8-7-6
15	2	4	6-7-3
23	3	1	9-11-14-13
24	4	1	9-10-12-11

## 9.2 Constructing a ContactSearch Object

The code fragment below represents the call (and error checking) to construct the ContactSearch object:

```
ContactSearch::ContactErrorCode error;
ContactSearch search_obj(
    dimensionality, number_of_states, number_of_entity_keys,
    number_of_node_blocks, node_block_types,
    number_of_nodes_in_blocks, node_exodus_ids, node_global_ids,
    number_of_face_blocks, face_block_types,
    number_of_faces_in_block, face_global_ids, face_connectivity,
    number_of_elem_blocks, elem_block_types,
    number_of_elems_in_blocks, elem_global_ids, elem_connectivity,
    number_of_nodal_comm_partners, nodal_comm_proc_ids,
    number_of_nodes_to_partner, communication_nodes,
    mpi_communicator, error );
if( error ){ // an error occurred on some processor
    int num_err = search_obj.Number_of_Errors();
    for( int i=0 ; i<num_err ; i++ )
        cout << search_obj.Error_Message(i) << endl;
    exit(error);
}
```

The data below represent the values of the arguments in the constructor:

```
dimensionality = 3
number_of_states = 1
number_of_entity_keys = 5
number_of_node_blocks = 1
node_block_types = { NODE }
number_of_nodes_in_blocks = { 14 }
node_exodus_ids = { 11, 8, 13, 1, 4, 17, 21, 41, 17, 33, 19, 27, 38,
                    16) }
node_global_ids = { (0,11), (0,8), (0,13), (0,1), (0,4), (0,17), (0,21),
                    (0,41), (0,17), (0,33), (0,19), (0,27), (0,38),
```

## Example

```
        (0,16) }
number_of_face_blocks = 4
face_block_types = { TRIFACEL3, TRIFACEL3, QUADFACEL4, QUADFACEL4 }
number_of_faces_in_block = { 4, 4, 1, 1 }
face_global_ids = { (0,1), (0,2), (0,3), (0,4), (0,5), (0,6), (0,7),
                   (0,8), (0,9), (0,10) }
face_connectivity = { [1, 5, 2, 2, 5, 3, 3, 5, 4, 5, 1, 4],
                     [4, 6, 3, 4, 8, 6, 8, 7, 6, 6, 7, 3],
                     [9, 11, 14, 13] , [9, 11, 12, 10] }
number_of_elem_blocks = 0
element_block_types = NULL
number_of_elems_in_block = NULL
element_global_ids = NULL
element_connectivity = NULL
number_of_nodal_comm_partners = 0
nodal_comm_proc_ids = NULL
number_of_nodes_to_partner = NULL
communication_nodes = NULL
mpi_communicator = 0
```

### 9.3 Adding an Analytic\_Surface

The next step is to add the analytic plane. Since we have already added four Face\_Blocks, the ID of the PLANE Analytic\_Surface will be 5. The code fragment (and error checking) to add this Analytic\_Surface is:

```
error = search_obj.Add_Analytic_Surface(
    analytic_surfacetype,
    data );
if( error ){
    int num_err = search_obj.Number_of_Errors();
    for( int i=0 ; i<num_err ; i++ )
        cout << search_obj.Error_Message( i ) << endl;
    exit(error);
}
```

The data needed to add the Analytic\_Surface are (see Table 11 for a description of the data):

```
analyticsurface_type = PLANE
data = { [0.0, 0.0, 0.0], [0.0, 1.0, 0.0] }
```

### 9.4 Search Data

The next step is to set the Search\_Data. For this example, assume the user only wants interactions for nodes of Face\_Block 2 against faces of Face\_Block 3, nodes of Face\_Block 3 against faces of Face\_Block 2 and nodes of Face\_Blocks 1 and 4 against the PLANE Analytic\_Surface. We will use a Search\_Normal\_Tolerance of 0.01 for interactions between the two bodies and a Search\_Normal\_Tolerance of 0.1 for the bodies against the PLANE Analytic\_Surface. We will use Search\_Tangential\_Tolerance values of half the respective Search\_Normal\_Tolerance values. Currently, a node only has one entity key

(this is a limitation of the current implementation and will be addressed in a future release). The entity\_key assigned to the node is from the first face it is connected to. As a result of this limitation, we must also allow interactions to be defined between nodes from face block 1 to interact with faces from face block 3 and nodes from face block 4 to interact with faces from face block 2. The call to add these data is:

```
search_obj.Set_Search_Data( Search_Data );
```

The search data array, with 2 x 5 x 5 values, is:

```
Search_Data = {
    0, 0.01, 0.005 // FB1 nodes against FB1 faces
    0, 0.01, 0.005 // FB2 nodes against FB1 faces
    0, 0.01, 0.005 // FB3 nodes against FB1 faces
    0, 0.01, 0.005 // FB4 nodes against FB1 faces
    0, 0.01, 0.005 // Analytic Plane against FB1 faces (don't exist)
    0, 0.01, 0.005 // FB1 nodes against FB2 faces
    0, 0.01, 0.005 // FB2 nodes against FB2 faces
    1, 0.01, 0.005 // FB3 nodes against FB2 faces
    1, 0.01, 0.005 // FB4 nodes against FB2 faces
    0, 0.01, 0.005 // Analytic Plane against FB2 faces (don't exist)
    1, 0.01, 0.005 // FB1 nodes against FB3 faces
    1, 0.01, 0.005 // FB2 nodes against FB3 faces
    0, 0.01, 0.005 // FB3 nodes against FB3 faces
    0, 0.01, 0.005 // FB4 nodes against FB3 faces
    0, 0.01, 0.005 // Analytic Plane against FB4 faces (don't exist)
    0, 0.01, 0.005 // FB1 nodes against FB4 faces
    1, 0.01, 0.005 // FB2 nodes against FB4 faces
    0, 0.01, 0.005 // FB3 nodes against FB4 faces
    0, 0.01, 0.005 // FB4 nodes against FB4 faces
    0, 0.01, 0.005 // Analytic Plane against FB4 faces (don't exist)
    1, 0.1, 0.05 // FB1 nodes against Analytic Plane
    0, 0.1, 0.05 // FB2 nodes against Analytic Plane
    0, 0.1, 0.05 // FB3 nodes against Analytic Plane
    1, 0.1, 0.05 // FB4 nodes against Analytic Plane
    0, 0.1, 0.05 } // Analytic Plane against Analytic Plane
```

## 9.5 Setting the Search Options

For this example, multiple interaction definition is necessary but normal smoothing is not needed. A value of 30 degrees will be used for the SHARP\_NON\_SHARP\_ANGLE. The code fragment to activate multiple interactions is

```
// Activate multiple interaction
error = Set_Search_Option(
    ContactSearch::MULTIPLE_INTERACTIONS,
    ContactSearch::ACTIVE,
    multiple_interaction_data );
if( error ){
```

## Example

```
int num_err = search_obj.Number_of_Errors();
for( int i=0 ; i<num_err ; i++ )
    cout << search_obj.Error_Message( i ) << endl;
exit(error);
}
```

where `multiple_interaction_data` is a pointer to the `SHARP_NON_SHARP_ANGLE` which has been set to 30 degrees. The code fragment to deactivate normal smoothing is

```
// Deactivate normal smoothing
error = Set_Search_Option(
    ContactSearch::NORMAL_SMOOTHING,
    ContactSearch::INACTIVE,
    dummy );
if( error ){
    int num_err = search_obj.Number_of_Errors();
    for( int i=0 ; i<num_err ; i++ )
        cout << search_obj.Error_Message( i ) << endl;
    exit(error);
}
```

Since normal smoothing is being deactivated, `dummy` is a pointer to double but will never be dereferenced so its value is irrelevant.

## 9.6 Specifying Configurations

At this point the topology is completely specified. The search object can be used to compute the interactions once the configurations are specified. Since we are going to perform a dynamic search, we need to specify the current and predicted configurations for the `Node_Blocks` (in this case only one block). The code fragment to set the configurations is:

```
// Supply the current position
for( int iblk=1 ; iblk<=number_of_node_blocks ; iblk++ ){
    error = search_obj.Set_Node_Block_Configuration(
        ContactSearch::CURRENT_CONFIG,
        iblk,
        current_positions[iblk-1] );
    if( error ){
        int num_err = search_obj.Number_of_Errors();
        for( int i=0 ; i<num_err ; i++ )
            cout << search_obj.Error_Message( i ) << endl;
        exit(error);
    }
    // Supply the predicted position
    error = search_obj.Set_Node_Block_Configuration(
        ContactSearch::PREDICTED_CONFIG,
        iblk,
        predicted_positions[iblk-1] );
    if( error ){
        int num_err = search_obj.Number_of_Errors();
        for( int i=0 ; i<num_err ; i++ )
            cout << search_obj.Error_Message( i ) << endl;
        exit(error);
    }
}
```

```

    }
}

```

The current and predicted positions for the nodes are shown in Table 15.

Table 15 Current and Predicted Positions for Example Problem

Node	Current Position	Predicted Position
1	{-1.1 0.1 0.0}	{-0.9 -0.1 0.0}
2	{ -1.1 0.1 1.0}	{-0.9 -0.1 1.0 }
3	{ -0.1 0.1 1.0}	{ 0.1 -0.1 1.0}
4	{ -0.1 0.1 0.0}	{ 0.1 -0.1 0.0}
5	{ -0.6 0.1 0.5}	{ -0.4 -0.1 0.5}
6	{ -0.1 0.6 0.6}	{ 0.1 0.4 0.6}
7	{ -0.1 1.1 1.0}	{ 0.1 0.9 1.0}
8	{ -0.1 1.1 0.0}	{ 0.1 0.9 0.0}
9	{0.1 0.1 0.0}	{ -0.1 -0.1 0.0}
10	{1.1 0.1 0.0}	{0.9 -0.1 0.0 }
11	{0.1 0.1 1.0}	{ -0.1 -0.1 1.0}
12	{1.1 0.1 1.0}	{0.9 -0.1 1.0 }
13	{0.1 1.1 0.0}	{-0.1 0.9 0.0 }
14	{0.1 1.1 1.0}	{ -0.1 0.9 1.0}

## 9.7 Performing the Search

The search can now be performed with the following code fragment:

```

error = search_obj.Dynamic_Search_2_Configuration();
if( error ){
    cout << "Error in Dynamic_Search:: Error Code = "
        << error << endl;
    int num_err = search_obj.Number_of_Errors();
    for( i=0 ; i<num_err ; i++ )
        cout << search_obj.Error_Message(i) << endl;
    exit(error);
}

```

## Example

### 9.8 Extracting Interactions

The following coding will extract both the NodeFace\_Interactions and the NodeSurface\_Interactions:

```
// Get the NodeFace_Interactions
int number_of_NFIs, NFI_data_size;
search_obj.Size_NodeFace_Interactions(
    number_of_NFIs,
    NFI_data_size);
if( number_of_NFIs ){
    int* NFI_node_block_ids = new int[number_of_NFIs];
    int* NFI_node_indexes_in_block = new int[number_of_NFIs];
    int* NFI_node_entity_keys = new int[number_of_NFIs];
    int* NFI_face_block_ids = new int[number_of_NFIs];
    int* NFI_face_indexes_in_block = new int[number_of_NFIs];
    int* NFI_face_procs = new int[number_of_NFIs];
    double* NFI_data = new double[number_of_NFIs*NFI_data_size];
    search.Get_NodeFace_Interactions(NFI_node_block_ids,
        NFI_node_indexes_in_block, NFI_node_entity_keys,
        NFI_face_block_ids, NFI_face_indexes_in_block,
        NFI_face_procs,NFI_data);
}

// Get the NodeSurface_Interactions
int number_of_NSIs, NSI_data_size;
search_obj.Size_NodeSurface_Interactions(
    number_of_NSIs,
    NSI_data_size );
if( number_of_NSIs ){
    int* NSI_node_block_ids = new int[number_of_NSIs];
    int* NSI_node_indexes_in_block = new int[number_of_NSIs];
    int* NSI_analyticssurface_ids = new int[number_of_NSIs];
    double* NSI_data = new double[number_of_NSIs*NSI_data_size];
    search.Get_NodeSurface_Interactions(NSI_node_block_ids,
        NSI_node_indexes, NSI_analyticssurface_ids, NSI_data );
}
```

Table 16 gives the data for the NodeFace\_Interactions and Table 17 gives the data for the NodeSurface\_Interactions.

Table 16 NodeFace\_Interactions for Example Problem

Node Block	Index in Block	Node Entity Key	Face Block	Index in Block	Local Coords	Gap	Unit Pushback Vector	Unit Surface Normal	Alg
1	3	2	3	1	1, -1	-0.2	-1, 0, 0	-1, 0, 0	3
1	4	2	3	1	-1, -1	-0.2	-1, 0, 0	-1, 0, 0	3
1	6	2	3	1	0, 0	-0.2	-1, 0, 0	-1, 0, 0	3

Table 16 NodeFace\_Interactions for Example Problem

Node Block	Index in Block	Node Entity Key	Face Block	Index in Block	Local Coords	Gap	Unit Pushback Vector	Unit Surface Normal	Alg
1	7	2	3	1	1, 1	-0.2	-1, 0, 0	-1, 0, 0	3
1	8	2	3	1	-1, 1	-0.2	-1, 0, 0	-1, 0, 0	3
1	9	3	2	1	0, 0	-0.2	1, 0, 0	1, 0, 0	3
1	11	3	2	1	0, 0	-0.2	1, 0, 0	1, 0, 0	3
1	13	3	2	2	0, 1	-0.2	1, 0, 0	1, 0, 0	3
1	14	3	2	3	0, 1	-0.2	1, 0, 0	1, 0, 0	3

Table 17 NodeSurface\_Interactions for Example Problem

Node Block	Index in Block	Surface ID	Gap	Interaction Point	Surface Normal
1	1	5	-0.1	-0.9, 0, 0	0, 1, 0
1	2	5	-0.1	-0.9, 0, 1	0, 1, 0
1	5	5	-0.1	-0.4, 0, 0.5	0, 1, 0
1	11	5	-0.1	-0.1, 0, 1	0, 1, 0
1	9	5	-0.1	-0.1, 0, 0	0, 1, 0
1	4	5	-0.1	0.1, 0, 0	0, 1, 0
1	3	5	-0.1	0.1, 0, 1	0, 1, 0
1	10	5	-0.1	0.9, 0, 0	0, 1, 0
1	12	5	-0.1	0.9, 0, 1	0, 1, 0

This completes the example for one time step. It is assumed the host code would take these interactions, enforce the constraints implied by these interactions and then integrate the governing equations to the next time step. At that point, the host code can supply the current and predicted configurations for the new time step and call the search again to define new interactions. This process can then be repeated until the analysis is complete.

## 9.9 ExodusII Output

An ExodusII output file can be created which contains the topology and interactions with the following code fragment

## Example

```
int iows = 8;
int compws = 8;
char OutputFileName[] = "contact_topology.exo";
int exodus_id=ex_create(OutputFileName,EX_CLOBBER,&compws,&iows );
if( search->Exodus_Output( exodus_id, time ) ){
    cout << "Error with exodus output" << endl;
    for( i=0 ; i<search->Number_of_Errors() ; i++ )
        cout << search->Error_Message(i) << endl;
}
ex_close( exodus_id );
```

Figure 17 shows plots from the ExodusII output for this example. The analytic plane is not shown in these plots because there is no way to include this plane in the ExodusII file.

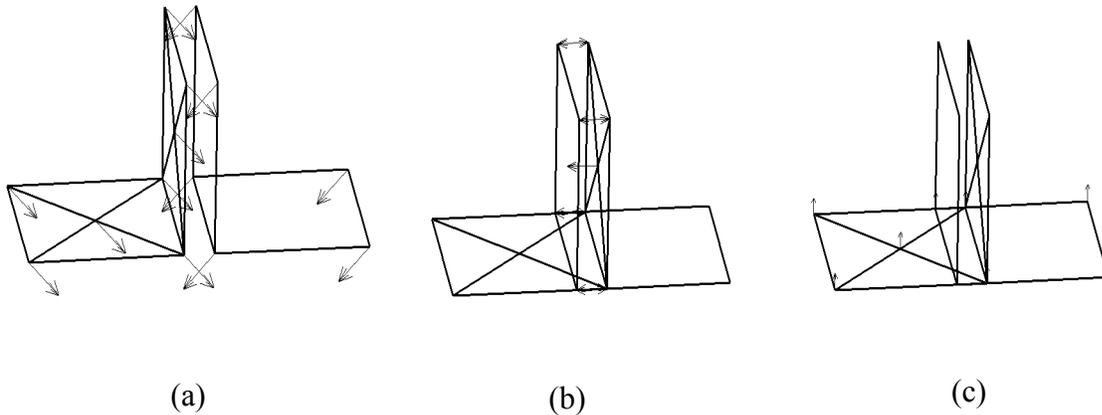


Figure 17 ExodusII Output for Example Problem

- The topology with a vector plot of displacement.
- NodeFace\_Interaction vector plot. Note the interaction vectors push back exactly to the opposing face.
- NodeSurface\_Interaction vector plot. The “top” of the vectors represent the location of the Analytic\_Surface.

## Appendix A: Glossary of ACME Terms

ACME - Algorithms for Contact in a Multiphysics Environment.

Analytic\_Surface - A rigid surface that can be described analytically by a geometric definition (e.g., planes and spheres).

ContactErrorCode - An error code returned by all public access functions in ACME.

ContactFace\_Type - The type of faces in a Face\_Block, currently QUADFACEL4, QUADFACEQ8, TRIFACEL3, or TRIFACEQ6.

ContactGapRemoval - The top level object constructed by a host application to determine a displacement increment that will remove initial gaps using interactions found by the ContactSearch object.

ContactNode\_Type - The type of nodes in a Node\_Block, currently only NODE. (NODE\_WITH\_SLOPE and NODE\_WITH\_RADIUS not yet available in this release.)

ContactSearch - The top-level object constructed by a host application to search for topological interactions.

ContactTDEnforcement - The top level object constructed by a host application to determine forces from topological interactions found by the ContactSearch object for use in transient dynamics equations.

Dynamic 2-Configuration Search - The search algorithm that uses a combination of a dynamic intersection and closest point projection to determine interactions.

Dynamic Augmented 2-Configuration Search - The search algorithm that uses contact forces from the last time step (from a ContactTDEnforcement object) to construct an augmented predicted configuration. The algorithm then determines interactions using this configuration with a combination of a dynamic intersection and closest point projection.

Entity\_Key - An identifier for a topological entity (currently node, face, or Analytic\_Surface) used to extract user-specified parameters from the Search\_Data array.

Face\_Block - A collection of faces of the same type that have the same Entity\_Key.

FaceCoverage\_Interaction - A set of data returned by ACME to the host code that contains the interacting face and the data describing the interaction (the contour of the uncovered portion of the face is described by the number of edges and edge nodes of that contour).

FaceFace\_Interaction - A set of data returned by ACME to the host code that contains the interacting face (slave face), a face with which it interacts (master face), and the data describing the interaction (the contour of the face/face overlap is described by the number of edges, the edge nodes, the overlap centroid, and a set of edge flags).

Gap - The distance between a node and a face, in the direction normal to that face in most cases, defined as positive if the node is not penetrating the face and zero or negative if the node is on or inside (penetrating) the face.

NODE - A traditional node with position and no other attributes.

Node\_Block - A collection of nodes of the same type. Currently, all node blocks must be of type NODE. All nodes that are connected to faces must be in the first Node\_Block. Nodes that are not connected to faces (i.e., SPH particles, Gauss points, etc.) must be placed in Node\_Blocks 2 through N.

NodeFace\_Interaction - A set of data returned by ACME to the host code that contains the interacting node, the face with which it interacts, and data describing the interaction (contact point in local coordinates, Normal\_Gap, unit pushback vector, unit surface normal, and algorithm used).

NodeSurface\_Interaction - A set of data returned by ACME to the host code that contains the interacting node, the Analytic\_Surface with which it interacts, and additional data describing the interaction (contact point in global coordinates, Normal\_Gap, and unit surface normal).

QUADFACEL4 - A 4-node quadrilateral face with linear interpolation.

QUADFACEQ8 - An 8-node quadrilateral face with quadratic interpolation.

Search\_Data - An array containing user-specified parameters (currently three: Interaction\_Status, Search\_Normal\_Tolerance and Search\_Tangential\_Tolerance) that must be set by the host code to control the search algorithms for all possible pairs of interacting topological entities.

Search\_Normal\_Tolerance - An absolute distance defined by the user to determine, in conjunction with any physical motion, whether two topological entities interact. This tolerance acts normal to the face.

Search\_Tangential\_Tolerance - An absolute distance defined by the user to determine, in conjunction with any physical motion, whether two topological entities interact. This tolerance acts tangential to the face.

Static 1-Configuration Search - The search algorithm that uses only one configuration to determine interactions using a closest point projection.

Static 2-Configuration Search - The search algorithm that uses two configurations, current and predicted, to determine interactions using a closest point projection.

TRIFACEL3 - A 3-node triangular face with linear interpolation.

TRIFACEQ6 - A 6-node triangular face with quadratic interpolation.

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