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Fluid Structure Interaction: 3D Numerical Simulation and Visualization of a Micropump

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Summary

The numerical treatment of coupled problems has turned out to be one of the principal challenges in numerical simulation. Due to the increasing demands for accuracy, the interactions of different physical phenomena can no longer be neglected or simplified, but have to be taken into account in detail. On the other hand, because of the variety of applications and due to the fact that modeling such a kind of interaction always requires a lot of experience from different scientific areas, the problem specific modeling and simulation of a coupled problem very often seem to be a too time-consuming process. Therefore, modular concepts which allow to profit from existing subproblem models or codes, resp., and to integrate those into an efficient coupling algorithm have to be developed.

In this paper, we study a modular approach for the 3 D numerical simulation of the fluid structure interaction in a valve-driven micropump that has been designed for medical and environmental applications. For the structural part, we use ADINA and MSC/NASTRAN. The fluid flow simulation is done with the MAC-based Navier-Stokes solver NaSt3D which has been developed at our department. The coupling itself is realized via an outer iterative scheme.

1 Introduction

Together with the increasing possibilities of numerical simulation in science and engineering, the demands for both accuracy of the calculations and complexity of the problems to be tackled grow as well. More and more, not only single devices, but whole systems consisting of several components and involving different physical phenomena are in the centre of interest. This can be seen, especially, in the area of microsystem technology [2, 22], where microminiaturized sensors and actuators are based on physical effects like fluid mechanics, structural mechanics, heat transfer, or electromagnetics, e. g. Furthermore, here, aspects of scaling can lead to a dominance of surface effects (which are often responsible for interactions) over volume dependent effects. Finally, the high integration density in microsystems often results in unintentional cross effects (thermal strains in smart sensors or cross talks between different electric conductors, e. g.). Therefore, the numerical simulation of such interactions or couplings gains more and more in importance, and its focus has shifted from problems like reservoir dam interaction or reactor safety to microtechnology [2, 8, 22, 23, 25, 27–29, 33, 34].

In this paper, we study parts of a valve-driven micropump [33, 34], i. e. the fluid structure interaction which occurs at the valve flaps and which is responsible for their opening and closing. In order to avoid a completely new and comprehensive modeling of the micropump, we apply a modular solution strategy, the so-called *partitioned solution* [6, 7], which allows us to profit from existing simulation codes for both the fluid and the structural part [4, 20]. For such an approach, the crucial task is the choice of an appropriate outer iteration that links the different codes and finally leads to a solution of the coupled problem. At the moment, the quasi-stationary iteration scheme is based on Gauß-Seidel-type or fix point methods.

Whereas the structural part is not too hard in this case and can be solved by almost any code for structural mechanics, the simulation of the fluid flow requires a code that can efficiently deal with varying geometries. However, due to the small dimensions, we do not encounter turbulence. So far, all experiments have been done with the codes NaSt2D/NaSt3D [9] which solve the incompressible Navier-Stokes equations with a marker-and-cell discretization scheme.

The remainder of this article is organized as follows. In Section 2, we give a short overview of coupled problems and their numerical solution, and we present and discuss the modular approach of the partitioned solution. Section 3 provides the most important properties of our model of the valve-driven micropump. Due to its importance, the fluid code is presented in detail in Section 4. In Section 5, finally, we discuss some aspects concerning the implementation of a modular coupled simulation, we describe the application of the modular solution strategy to this special case of fluid structure interaction, and we show some results and visualizations of numerical experiments.

2 Coupled Problems and their Numerical Solution

The variety of examples for coupled problems from all kinds of areas of application (cf. Figure 1) has led to a very broad interpretation of the term coupled problems and to the development of quite different techniques for their numerical treatment [13, 15, 19, 35, 36]. A first kind of a unifying approach was done by Zienkiewicz in [35], where he defines a coupled problem to be a problem with bidirectional interactions of (usually different) physical effects without any possibility of an independent solution of a subproblem on its respective domain. Based on this definition, Zienkiewicz distinguishes between two classes of coupled problems: those with totally or partially overlapping domains and those with non-overlapping domains. In the first case, the coupling takes place via differential equations that, usually, refer to different underlying physical phenomena. The second class, however, is characterized by a coupling that occurs on the domain interfaces, i. e. via boundary conditions. Here, both problems with different underlying physics or different variables (fluid structure interaction, e. g.) and problems with identical physics and variables (structure structure interaction, e. g.) exist.

Concerning the modeling and numerical simulation of coupled

components / kind of coupling	structural dynamics	heat conduction	fluid dynamics	electromagnetics
structural dynamics		- resonators (thermally induced high frequency vibrations) - thermal actuators	- accelerometers - gyroscopes - valves, pumpes	- sensors with capacitive detection - electrostatic and piezoelectric actuators
heat conduction	thermo-elasticity h→s: material law s→h: energy dissipation		- microcooler - flow- and thermal sensors	- thermopiles (electrical heating with integrated resistors) - thermal actuators (pump actuation, resonators)
fluid dynamics	f→s: surface forces s→f: - geometry - boundary cond.	coupled by the energy equation		- sensors and pumps working with the electrohydrodynamic principle
electromagnetics	e→s: surface and volume forces s→e: - geometry - moving conductor	e→h: electromagnetic loss h→e: material properties	electrohydrodynamics e→s: surface and volume forces s→e: - geometry - moving conductor	

Figure 1 Examples of interactions and corresponding devices

problems, two principal approaches have been established. A *joint* or *simultaneous* solution strategy combines the models of the different subproblems (either on the continuous or on the discrete level) via the respective coupling conditions in order to get a comprehensive model for the coupled problem, which is afterwards tackled numerically or solved, resp., as a whole (see [8, 30], e. g.). In contrast to that, the *partitioned* solution strategy [2, 6, 7, 23] is based on a strictly modular approach. There is no joint model, neither continuous nor discrete, but the coupled problem is solved by an *outer iteration* for the coupling and by almost arbitrary inner solution processes for each single subproblem (cf. Figure 2). The coupling is realized via changing boundary conditions, geometries, or parameters after each step of the outer iteration. Concerning the outer iteration, SOR-type methods are the state of the art [2, 4, 6, 7, 20]. However, the convergence behaviour of such methods can not be guaranteed in general [31]. Therefore, more robust iteration schemes have to be developed. Here, techniques for both linear [12] and nonlinear systems [17, 21] can be the starting point. As a first step, cg- and GMRES-based

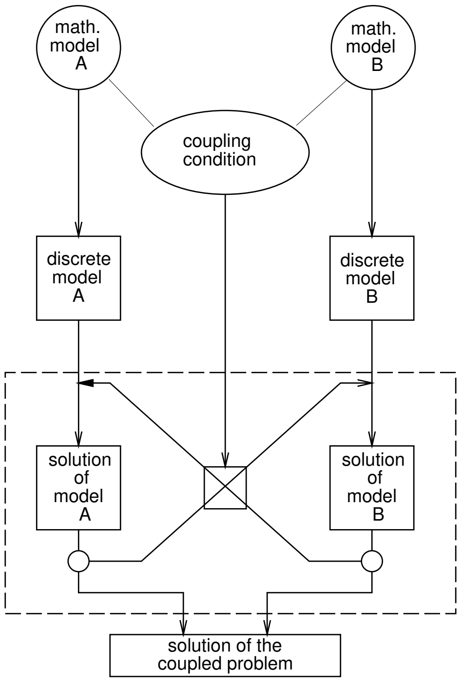


Figure 2 Partitioned solution

methods have been studied in [1]. Obviously, the main advantage of the partitioned solution scheme is its flexibility concerning both the problems to be solved and the codes to be used.

Besides the construction of the outer iteration scheme, there are the tasks of developing a suitable variable transformation at domain interfaces (in the case of non-matching discretizations, e. g.) and of the construction of error indicators and estimators for the overall procedure in order to be able to decide which subproblems have to be solved more exactly. Furthermore, the communication between the different solvers at the interfaces as well as the control of the overall procedure have to be organized, and an efficient implementation of a coupling environment has to be designed. A first and crucial task, however, is the identification and separation of appropriate mathematical models for the single effects and for the respective couplings. To this end, we define a coupled problem to consist of n subproblems $\mathcal{P}_i$, $1 \le i \le n$,

$$L_i[\Pi_i,\mathrm{K}_i](u_i) \;=\; 0 \qquad \text{on} \;\; \Omega_i, \tag{2.1}$$

and of m coupling conditions $\mathcal{C}_k$, $1 \le k \le m$,

$$C_k(u_1,\ldots,u_n,\mathrm{K}_1,\ldots,\mathrm{K}_n) \;=\; 0 \qquad \text{on} \;\; \Gamma_k. \tag{2.2}$$

Here, L_i denotes the operator of subproblem i, u_i the corresponding unknowns, and Ω_i the underlying domain. The operator L_i depends on two sets of parameters, the coupling ones (K_i) and the non-coupling ones (Π_i). The coupling equations (2.2) combine either the subproblem variables and the coupling parameters (parameter coupling: thermo-mechanical problems, e. g.) or the subproblem variables and changes in the underlying geometry (geometry coupling: fluid structure interaction, e. g.). The coupling domains or interfaces Γ_k are subsets of the union of the domains Ω_i of the involved subproblems $\mathcal{P}_i$. In the outer iteration scheme for the solution of the coupled problem, the subproblem equations (2.1) are solved by suitable available codes, whereas the coupling equations (2.2) have to be discretized and solved separately.

Finally, note that such a formulation opens the way to graph theoretical investigations, starting from a graph for the coupled problem where the nodes represent the subproblems $\mathcal{P}_i$ and the edges denote the couplings $\mathcal{C}_k$. Obviously, if n_k subproblems are involved in coupling $\mathcal{C}_k$, then $\mathcal{C}_k$ results in a complete subgraph of the respective n_k subproblems. If there are both uni- and bidirectional interactions, we have to work with directed graphs, if only bidirectional couplings occur, non-directed graphs are sufficient. A detailed analysis of a coupled problem's graph can give additional information concerning the complexity of the problem (are there cycles, is the graph reducible?) and, thus, some hints concerning the appropriate iterative scheme. Furthermore, in order to be able to choose a suitable and efficient outer iteration for a given coupled problem, the couplings have to be characterized further. Up to now, there exists no general concept of how to define and to determine weak or strong couplings and of how to distinguish between high-frequency couplings that need a very fine discretization of C_k and low-frequency couplings for which a few (coarse) grid points are sufficient. Those considerations are in the centre of our present work in this area.

3 The Micropump

Until now, several variants of micropumps have been developed differing mainly in the actuation unit, which is responsible for the fluid to flow, and in the regulation unit, which determines the flow's direction. For such pumps, the field of application ranges from medical drug infiltration systems [25] to chemical analysis in environmental technology. As we are primarily interested in fluid structure interactions, we decided to study a valve-driven micropump with passive check valves. Here, the interaction is crucial for the operation of the pump. Furthermore, there are a lot of experimental investigations and results [33, 34].

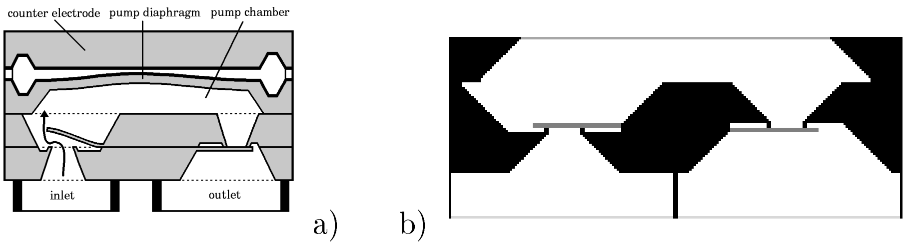


Figure 3 (a) Sketch of the structure of a valve-driven micropump [34], (b) geometric model used for the numerical simulation

The principal structure of a valve-driven micropump is shown in Figure 3. The inlet and the outlet (usually connected to the surrounding fluidic system via flexible hoses) are placed on the lower left-hand and on the lower right-hand side, resp. The upper part forms the actuation chamber where the fluid flow is induced by the oscillation of a diaphragm actuated by an external force (electrostatically, e. g.). When the membrane moves outward, the resulting low pressure causes the fluid to flow into the chamber. Moving inward, the membrane extrudes the fluid. In normal operation mode, the valves are bent in a way that regulates the flow from the inlet channel into the pump chamber and from the pump chamber into the outlet channel. The dimensions and some characteristic physical parameters of the pump described in [34] are itemized in Table 1.

Since our approach bases on the use of separate codes for the different physical disciplines, we have to consider the peculiarities of

fluid domain	
dimension	$7 \times 7 \times 2$ mm^3
material	ethanol
viscosity	$1.2 \cdot 10^{-3}$ Pa s
density	$7.89 \cdot 10^3$ kg/m^3

valve flaps	
dimension	$1.7 \times 1.0 \times 0.01$ mm^3
material	silicon
Young's modulus	$1.7 \cdot 10^{11}$ Pa
Poisson ratio	2.79

Table 1 Physical parameters of the fluid mechanical and the structural mechanical problem

each subproblem in order to select appropriate solvers. In our case, the elastomechanical problem is quite simple, since the dimension of this problem can be reduced due to the small gauge of the flaps. Thus, for a 3 D simulation, only the 2 D plate equation has to be solved, and in the reduced 2 D model of the pump, only the 1 D beam equation has to be considered. Therefore, almost any (commercial) code can be applied. In order to show the modularity of our approach, we chose ADINA for the 2 D computations and MSC/NASTRAN for the 3 D case.

The fluid flow is characterized by the use of ethanol, by the pump's small dimensions, and by the low occurring velocities. Thus, the fluid is viscous and incompressible, and the flow is laminar and transient. As an important requirement, the fluid solver should be able to deal with varying and moving obstacles in an efficient way. I. e., there should not be a significant overhead due to a repeated grid generation, e. g. Therefore, we chose the fluid code NaSt2D/NaSt3D, which will be described in detail in the following section.

4 The Fluid Model and Code

The fluid flow is described by the incompressible, transient Navier-Stokes equations

$$\rho\left(\frac{\partial \vec{v}}{\partial t} + \nabla(\vec{v} \otimes \vec{v})\right) = -\nabla p + \mu \triangle \vec{v} + \rho \vec{g}\,,^{1} \qquad (4.3)$$

$$\operatorname{div} \vec{v} = 0, \qquad (4.4)$$

where $\vec{v}$ denotes the velocity, p the pressure, $\vec{g}$ external forces (gravity, e. g.), ρ the constant density, and μ the dynamic viscosity of the fluid. Moreover, initial and boundary conditions such as no-slip, inflow, or outflow must be supplied.

Our CFD code NaSt2D/NaSt3D uses the marker-and-cell (MAC) scheme introduced in [14]. It is based on a finite difference discretization on a staggered equidistant grid. Although this scheme is very simple, it is quite flexible for describing complicated and moving fluid domains. For the discretization, the fluid domain is embedded into a rectangular basic domain, and the cells of this basic domain are flagged whether they are fluid cells, obstacle cells, or even empty cells for free boundary problems (see Figure 4). For the type of a cell, it is decisive in which domain the midpoint of the cell is situated.

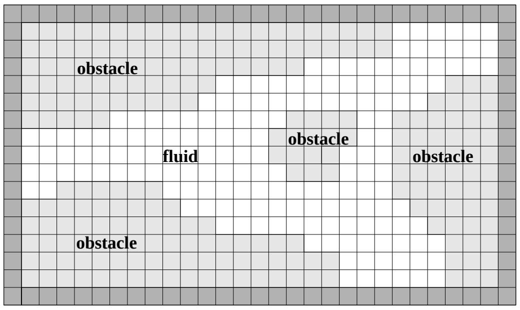


Figure 4 Embedding of the fluid domain into a rectangular domain

The time derivative in (4.3) is discretized by a simple explicit Euler step. In the time step $t_n \to t_{n+1}$, we first compute an intermediate velocity field $\vec{v}^*$ by means of the momentum equation (4.3) and by neglecting the pressure p:

$$\vec{v}^* = \vec{v}^{(n)} + \delta t \left(\frac{\mu}{\rho} \triangle \vec{v}^{(n)} - \nabla(\vec{v}^{(n)} \otimes \vec{v}^{(n)}) + \vec{g} \right). \qquad (4.5)$$

[1] $\vec{v} \otimes \vec{v}$ denotes the tensor product of two vectors which gives a matrix with elements $(\vec{v} \otimes \vec{v})_{i,j} := v_i v_j$.

This intermediate velocity field is then corrected by the pressure gradient to obtain the velocity at time step t_{n+1}:

$$\vec{v}^{\,(n+1)} = \vec{v}^{\,*} - \frac{\delta t}{\rho} \nabla p^{(n+1)}. \tag{4.6}$$

Finally, to satisfy the continuity equation (4.4) for $\vec{v}^{\,(n+1)}$, the pressure $p^{(n+1)}$ has to fulfil

$$\triangle p^{(n+1)} = \frac{\rho}{\delta t} \nabla \cdot \vec{v}^{\,*}. \tag{4.7}$$

This Poisson equation is solved by successive over relaxation (SOR). At the boundary of the fluid domain, we set $\vec{v}^{\,*} := \vec{v}^{\,(n+1)}$, such that homogeneous Neumann boundary conditions $\partial p^{(n+1)}/\partial n = 0$ follow from multiplying (4.6) with the normal $\vec{n}$ at the boundary.

The discretization in space is done by central differences for the continuity equation (4.4) and by second order derivatives in the momentum equation (4.3), whereas the convective part is discretized by flux blending, i. e. a mixture of central and upwind differences. According to the staggered grid scheme, the continuity equation (4.4) is discretized at the cell centers, and the momentum equation is discretized at the midpoints of the cell faces (see [10] for details).

Moreover, some stability conditions on the step sizes δt in time and $\delta x, \delta y, \delta z$ in space must be satisfied, namely the Courant-Friedrichs-Lewy (CFL) conditions

$$\frac{2\delta t\, \mu}{\rho} < \left(\frac{1}{dx^2} + \frac{1}{\delta y^2} + \frac{1}{\delta z^2} \right)^{-1},$$

$$|u_{max}|\, \delta t < \delta x, \qquad |v_{max}|\, \delta t < \delta y, \qquad |w_{max}|\, \delta t < \delta z,$$

where $|u_{max}|$, $|v_{max}|$, and $|w_{max}|$ denote the maximal absolute values of the velocity components u, v, and w, $\vec{v} = (u,v,w)^T$, occurring in the grid.

As boundary values, we need the velocity values at the boundary faces, i. e. at the faces between fluid cells and non-fluid cells, and at faces between two non-fluid cells adjacent to fluid cells. In the first version of NaSt2D/NaSt3D, we approximated the boundary of the fluid domain by a surface composed of cell faces, i. e. we set the velocity values at faces between fluid and non-fluid cells to zero for no-slip walls, for example. This method can be considered as a constant interpolation of the boundary values from the exact boundary to the boundary faces, which leads to an approximation order of $O(\delta x)$.

This simple scheme enables us to simulate fluid flow through complicated geometries like porous media (see Figure 5), the transport of chemical pollution (see Figure 6), temperature-driven flow (see Figure 7), and free boundary problems like the free surface flow over a backward facing step (see Figure 8).

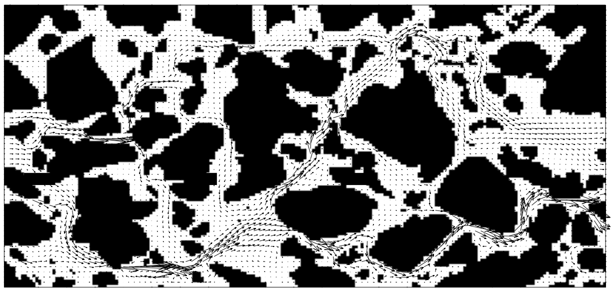
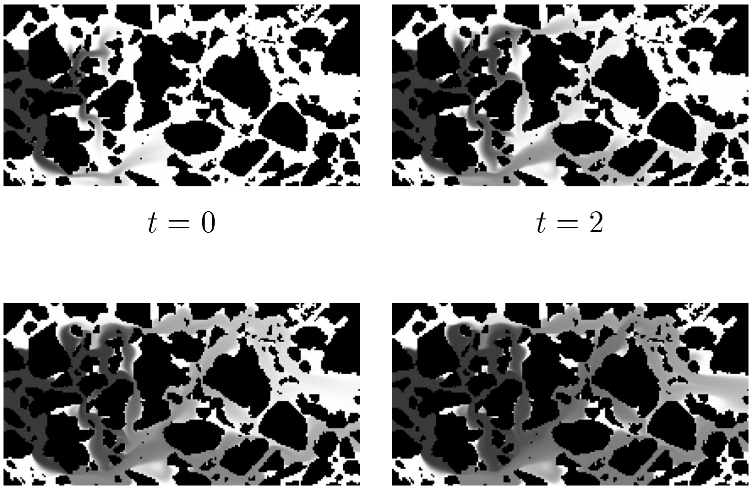


Figure 5 Flow through a porous medium (velocity field)

But for problems with moving obstacles like the valve flap, e. g., in order to avoid too small cells, the accuracy of our scheme has to be improved, because we can only simulate a discrete movement of the obstacles, i. e. we can only decide whether an obstacle moves a whole cell or is at rest.

Therefore, in [3] a better approximation of the boundary values was implemented which is based on the GENSMAC scheme [26]. Here, interpolation techniques are used to get the values on boundary faces from values at the exact boundary and nearest velocity values at faces between two fluid cells. Using central differences to discretize the convective terms of the momentum equations, an approximation order of $O(\delta x^2)$ results [3]. To describe the location of an obstacle, it is possible to use analytical functions, one- or two-dimensional



$t = 0$ $t = 2$

$t = 5$ $t = 10$

Figure 6 Pollution transport through a porous medium (time dependent concentrations, velocity field shown in Figure 5)

meshes in 2 D or 3 D, respectively, or volume of fluid techniques [16, 32].

Besides this extension concerning a better approximation of the boundary, some other work was done with NaSt2D/NaSt3D. In [11], an algebraic multigrid solver was implemented to solve the pressure equation and also the momentum equations in a semi-implicit time discretization of the momentum equations, the code was parallelized in two [10] and three space dimensions [18], and we are working on fluid flow problems with phase change, namely the solidification of an undercooled melt.

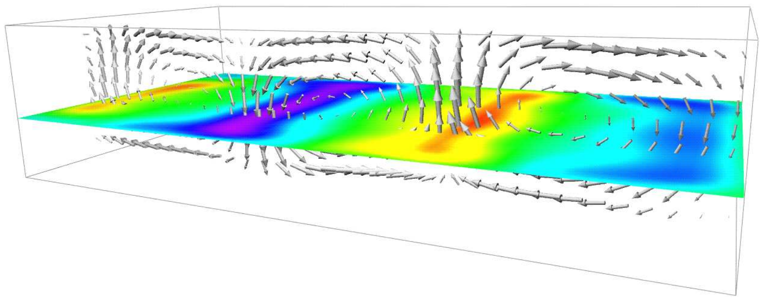


Figure 7 Rayleigh-Bénard flow: Flow driven by a hot bottom and a cold top wall (velocity field in a vertical, temperature distribution in a horizontal plane)

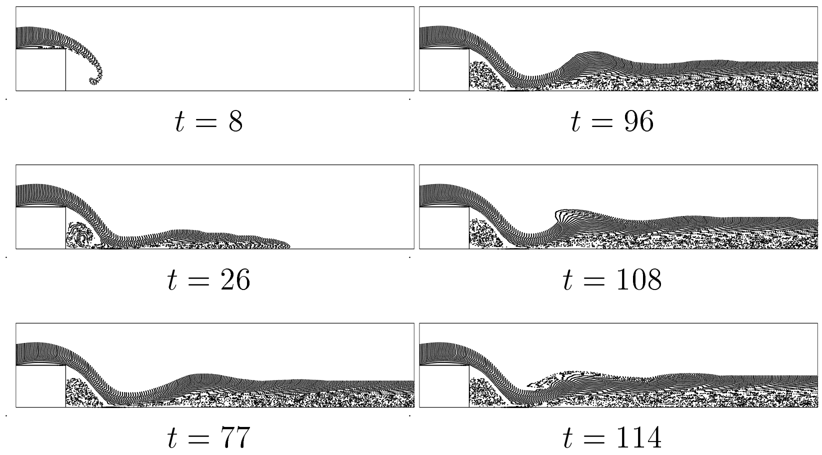


Figure 8 Free boundary flow over a backward facing step

5 Implementation, Experiments, and Visualization

The principle of the *partitioned solution* puts us in a position to avoid the full implementation of problem specific software by using a modular structure. Hence, we gain a better efficiency concerning flexibility and, therefore, modeling time and cost. Furthermore, the use of existing codes for the solution of the subproblems and for the visualization permits an adaptation to new problems and new developments without great efforts. First approaches in developing a modular software environment for the solution of coupled problems were carried out in the late 1970s [5], followed by the MEMCAD initiative [24], e. g. Increasing computing capacities and improved numerical algorithms add interesting new features. A combination with modern paradigms in computer science like parallel computing, client server systems, distribution over networks, and the usage of remote resources is quite promising. However, this requires to master heterogeneous computer, network, and software environments.

To handle heterogeneity, we designed an open environment able to control many quite different modules cooperating to solve coupled problems. With the separate tools, we are able to take advantage of distributed computing within a local area network without great efforts. The single modules can be assigned to five units (see Figure 9). The *input unit* collects and assembles the input data supplied by the user or by preceding software. The results are provided by the *output unit* for further processing. The *couple unit* is responsible for data maintenance as well as for the interaction and data exchange over the interfaces to the other units. It passes the appropriately converted data to the *tool unit*, which performs the required task (problem solving, visualization, e. g.). The couple unit is driven by the *control unit* according to the coupling algorithm. This algorithm is written in a script-like *couple language*, so that it can be easily modified.

The main problem in designing such a polymorphic environment is the definition of appropriate interfaces between the different units, especially for the integration of commercial software tools into the environment. Here, due to the prevalent unavailability of the source

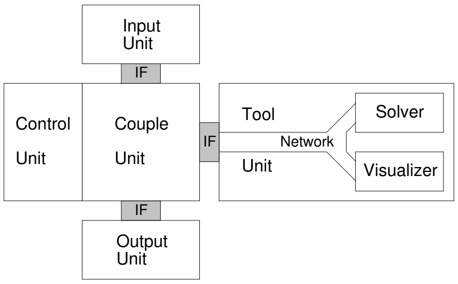


Figure 9 The five units of the modular system

code, manipulations therein are mostly impossible. For the combination of different data formats used in the various tools, it seems to be most appropriate to choose a unified representation of the parameters, the variables, and the geometry. In the prototype version, the data base in the centre of the system (i. e. the couple unit) consisting of the full data necessary for the simulation is realized as a file in tagged file format called *Coupled System Data Format (CSDF)*. As part of the CSDF, the geometry is represented as a structured quadrilateral grid or hexahedral cell structure, resp., to be equipped with a data structure that efficiently supports variations of the geometry. The physical parameters are transformed into standardized units (possibly in usage of reference values). Data necessary for visualization is also included. Hence, the visualization can be accomplished while or after processing the data, and an analysis or even an interactive modification of the problem parameters become possible.

According to our iterative coupling strategy, the mode of operation for the solution of a coupled problem consisting of n subproblems $\mathcal{P}_i$, $1 \le i \le n$, with the help of the respective solvers S_i has the following structure:

- collection and assembly of data with conversion into CSDF
- loop (outer iteration):
  - extraction and preparation of data for solver S_i, $1 \le i \le n$
  - solution of problem $\mathcal{P}_i$, $1 \le i \le n$
  - conversion and integration of results into CSDF
  - solution of coupling equations C_k, $1 \le k \le m$

- output of data in appropriate format for further processing

Now, let us turn to our example. In terms of the notation introduced in Section 2, the operators of the subproblems describing the fluid structure interaction are defined as follows:

- $L_1\left[\Pi_1, \{\tilde{p}\}\right](u) := S[\Pi_1](u) - \tilde{p}$ in the fluid domain,
- $L_2\left[\Pi_2, \{\tilde{u}\}\right](p, v) := F_{\tilde{u}}[\Pi_2](p, v) - w_0$ in the flaps,
- $C_1(p, \tilde{p})$ extracting the load in the structural model from the pressure field in the fluid model,
- $C_2(u, \tilde{u})$ modifying the geometry of the fluid model according to the deflection of the structure.

Here, u represents the displacement of the flaps as the unknown for the structural problem and $\tilde{u}$ the displacement as a parameter of the fluid problem. p and v stand for the pressure and velocity of the fluid, resp., and $\tilde{p}$ for the load affecting the flaps. S denotes the model for structural mechanics, Π_1 the set of inner parameters for S containing boundary conditions and the Young's modulus, e. g. Finally, $F_{\tilde{u}}$ describes the model for fluid dynamics (depending on the displacement), Π_2 the set of inner parameters for $F_{\tilde{u}}$ like the viscosity and density, e. g., and w_0 the boundary conditions for the fluid flow.

As this system is not separable, we examined approaches like Block-Gauß-Seidel (i. e. alternate solution of the two subproblems) and Block-Jacobi iterations (i. e. concurrent solution of the subproblems). A close inspection of the Block-Jacobi scheme shows that it results in two complete Gauß-Seidel schemes not interacting with each other [20].

Using the Block-Gauß-Seidel scheme, the loop for the outer iteration in the mode of operation described above has to be adjusted accordingly. For the micropump, we start with both flaps closed and a given pressure and velocity distribution. The pressure difference at the flaps is regarded as a load impacting them and, therefore, is used as an input for the structural mechanics solver, which provides us with a new shape of the flaps' geometry. This new geometry is now passed to the fluid dynamics solver that calculates new pressure and velocity values according to the changes in geometry and boundary conditions, and so on. This procedure was first applied to a rudimentary 2 D model of a pump unit (see Figure 10 (left)) [20]. Afterwards, an improved model with a more realistic geometry in two and three dimensions (see Figure 10 (right)) and with parameters according to micromechanics was developed [4].

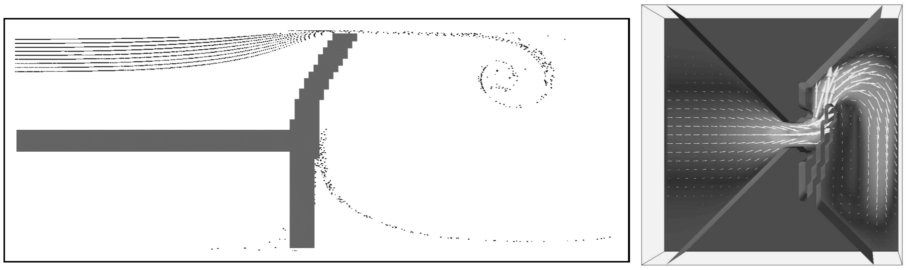


Figure 10 Draft 2 D geometry of a pump (left) and improved 3 D geometry of an inlet valve (right)

To model the time behaviour, we started with the interaction of a stationary fluid flow and a time independent flap displacement. In order to realize a transient simulation, a variation of the global boundary conditions (i. e. at the outer boundaries of the overall geometry) and the application of one outer iteration has to take place in every time step. Since the effects of these different modifications get mixed up that way, a closer survey of the particular influences is prevented. Therefore, we decided to pursue a quasi-stationary strategy first by introducing certain points at which the global boundary conditions are reconfigured. For each so-called *reconf point*, we apply a certain number of outer iterations (with fixed global boundary conditions), in order to mute the effects of occurring oscillations in the flap displacement. Due to the altered flap geometry, the Navier-Stokes equations have to be solved in each outer iteration. To accomplish this task, a varying amount of time steps with several SOR iterations for the pressure equation in the fluid solver is necessary. Hence, we get a hierarchy of four nested loops:

- inner iterations: solution of the pressure equation
- time steps: solution of the Navier-Stokes equations
- outer iterations: coupling of the interacting subproblems

- reconf points: modification of the global boundary conditions

Concerning the global boundary conditions, the influence of the actuation unit is modelled by velocity boundary conditions, while the changes of the geometry at the diaphragm are neglected, since its maximum expansion is only about 1/50 of the maximum flap displacement. The fluidic system connected to the pump unit is modelled by pressure boundary conditions for the global counter pressure [33]. The pressure declension between outlet and inlet has to be considered, since the behaviour of the pump depends on its value. Because of a still quite coarse approximation of the geometry, some details like the deflection of the flaps in reverse direction as well as their inertia are not yet taken into account.

As mentioned above, we use NaSt2D/NaSt3D for the solution of the fluid problem. For structural mechanics, a solver for the beam equation or ADINA are used for the 2 D case and MSC/NASTRAN for the 3 D case. The tools used for visualization are IDL for 2 D and IRIS EXPLORER for 3 D. Our visualizations focus on the fluid flow, since we are mainly interested in the behaviour of the fluid inside the pump chamber and in the pump's throughput. The representation of the corresponding quantities is done by various standard techniques as provided by the visualization packages including isolines/isosurfaces, vector fields, colour slices, and particle tracing (path- and streaklines, e. g.). The evolution in time is visualized by a series of single frames created at each reconf point with the techniques mentioned above that are combined to an animation sequence.

In our experiments, we use a maximum resolution of 200×80 cells for the 2 D case and $120 \times 60 \times 20$ cells for 3 D with a minimum mesh width of 25 μm. Since obstacle cells that are only adjoining at their corners are prohibited, the thickness of the flaps has to be at least two cells. However, these oversized flap extensions appear to have a negligible influence on the fluid flow. Following [33], for the global boundary conditions the pressure difference between outlet and inlet is set to 20 hPa, and the maximum velocity at the membrane is adjusted according to the pump frequency. We assume that the periodic behaviour of the membrane causes a sinusoidal alteration of the velocity at this boundary. To simulate a pump frequency of 25 Hz, for example, we subdivide each period by 20 reconf points with five outer iterations in-between. Hence, the time steps have to add up to $4 \cdot 10^{-4}$ s. Results for this configuration are shown in Figures 11 and 12 for 2 D. In order to reduce the extensive computation times, a coarser discretization in space and time was chosen for the 3 D case shown in Figure 13. Due to heavy oscillations in the flap motion, the deflection was restricted to a maximum displacement of one cell per outer iteration. As we perform several outer iterations for each reconf point, a sufficient mobility is guaranteed, nevertheless. The deflection of the flaps' tips at each outer iteration is shown in Figure 14. Note the obviously different behaviour of the two flaps.

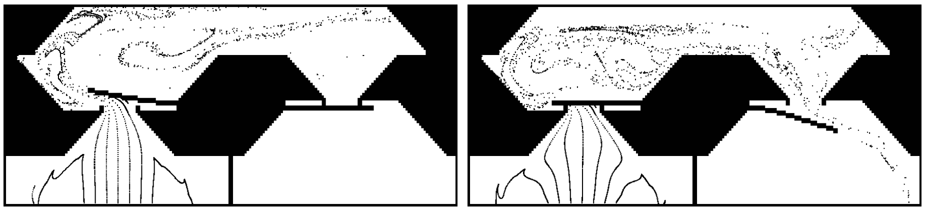


Figure 11 Snap shots of particles during the inlet and the outlet phase

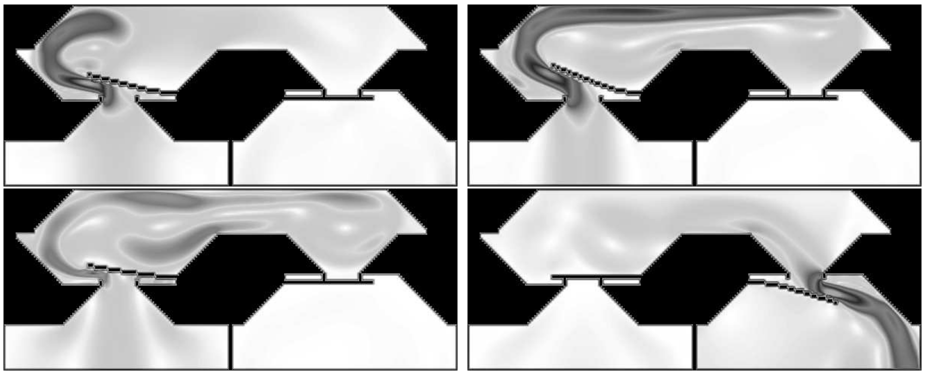


Figure 12 Four states in a period: absolute values of the velocity

The runtime for one outer iteration in the 2 D case takes about two minutes on a SGI Indy workstation (MIPS R4600PC, 100MHz). This leads to a total computing time of ten hours for three periods. The solution for the fluid problem consumes about 85 % of

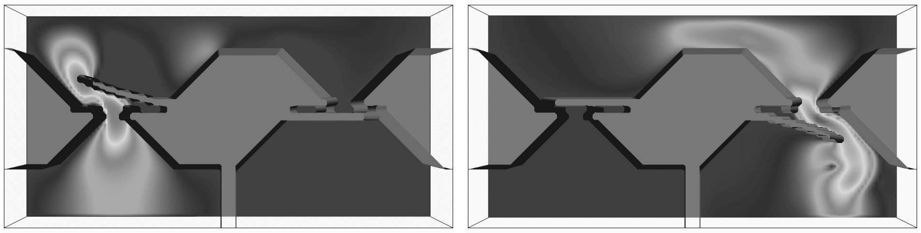


Figure 13 Absolute values of the velocity during the inlet and outlet phase (3 D)

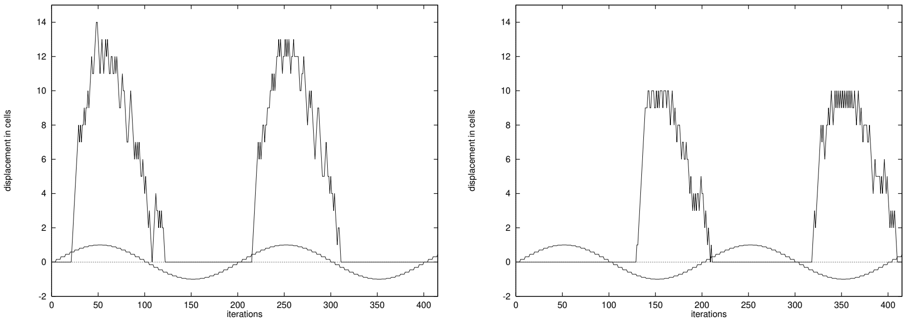


Figure 14 Displacement of the flap tips (1. and 2. period) at the inlet (left) and outlet (right) and progression of the velocity boundary conditions (normalized), simulating the oscillating membrane

the total computation time. As the structural mechanics problem is quite simple, the time for determining the new flap position is less than 5 %. The remaining 10 % are necessary for iteration procedures, coupling calculations, and data handling. Therefore, apart from the inevitable switch to a fully transient coupling, further optimizations have to concentrate on the solution of the fluid part. The improvements mentioned in Section 4 concerning a better approximation of the geometry, adaptivity of the solver, semi-implicit time discretization, and multigrid methods as well as parallelism are already examined and will be applied together with a usage of high performance computers in the near future. In spite of the strong imbalance in the complexity of the two subproblems, the examination of the fluid structure interaction in our example already shows the potential of the modular solution approach for the numerical simulation of coupled problems.

6 Concluding Remarks

In this article, we studied the fluid structure interaction of a valve-driven micropump. For the modular 3 D quasi-stationary numerical simulation of this coupled problem, we used the partitioned solution approach which is based on a separation of the solution of the subproblems (done by the structural solvers ADINA and NASTRAN and the fluid code NaSt3D) from the numerical treatment of the coupling equations in an outer iteration. The partitioned solution strategy reduces the modeling of a coupled problem to the modeling of the interaction itself, whereas, for the solution of each subproblem, existing mathematical models and codes can be used. First experiments with SOR-type outer iterations in the fluid structure case and with more general cg- and GMRES-based iterative schemes in the case of structure structure interaction show quite promising results.

For the future work, we will focus on a fully transient simulation and on the development of efficient and robust schemes for the outer iteration that allow to take into account the coupling characteristics of a given coupled problem.

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