

# INFRA

## Laurent

Trucheteries : pour faire des trucheteries au plotter ou à la brodeuse, il faut joindre des chemins disjoints avec vtype :

```
vtype read truchet_094.svg linemerge linesimplify -t 0.05 write truchet_94_merge.svg
```

## Infrabuble

<https://dev.laurent-malys.fr/bacasable/infra/>

## Multitude

<https://multitude.labomedia.org/>

<https://multitude.exsitu.xyz/v/map/19255da86d5b11f61>

## Dessins génératifs

Broderie + upcycling : [https://www.instagram.com/p/C58HraKiuYE/?img\\_index=1](https://www.instagram.com/p/C58HraKiuYE/?img_index=1)

Trucs à broder: <https://dev.laurent-malys.fr/harmono-bro/>

## Infra PickUp



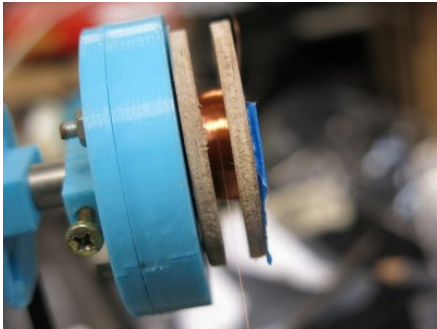
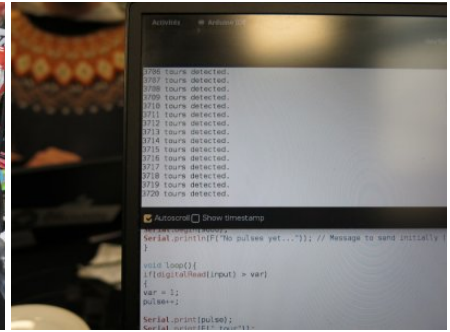
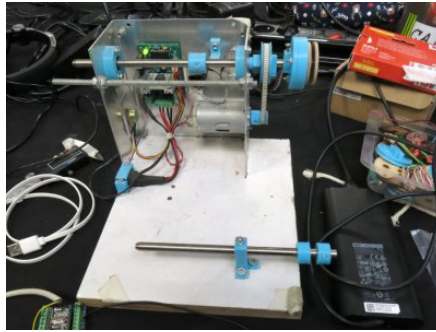
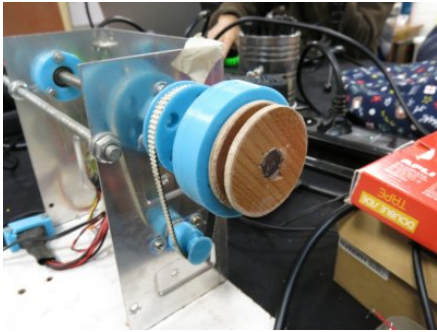
Profiter de ces beaux jours d'automne pour se chauffer au néons et ressortir la petite [bobineuse](#) pour créer un mirco

## la base infrastructurelle

- Deux disques de cp plaqué de 3 mm découper à la scie cloche
- Un aimant Alnico de 10mm de diamètre
- Du fil enamel de 0,063mm de diamètre
- Une plaque rectangulaire pour insérer les œillets et fixer le câbles audio

## le bobinage

- Un petit programme arduino pour compter les tour de bobines (grâce à un aimant placer sur l'axe de rotation et interrupteur reed)
  - récupérer ici : <https://forum.arduino.cc/t/simple-pulse-counter/519930>
- Environs 3500 tours



## assemblage

- La bobine et la base sont collés à l'epoxy



## trempage

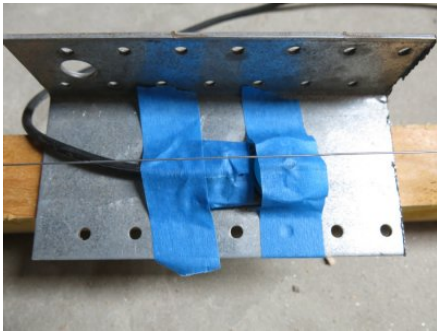
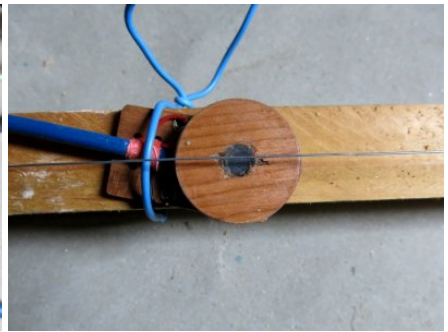
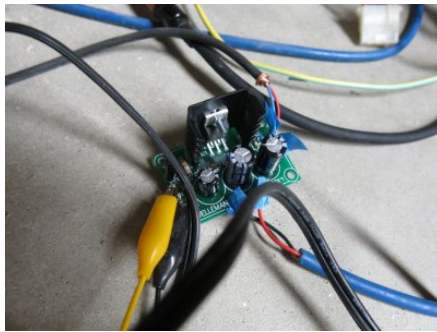
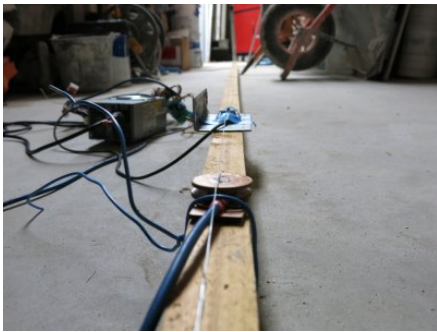
- Pour donner à l'ensemble un peu d'homogénéité et surtout protéger la bobine le tout est laissé trempé dans de la paraffine jusqu'à temps qu'il n'y ai plus de petites bulles



## essai infrabassique avec retour d'informations



- Ça fonctionne plutôt bien au niveau des infras
- Ajout d'un second micro (caché sous le scotch bleu)
- Câblage du gros micro et du petit avec un ampli mono 7W pour créer un feedback de résonances

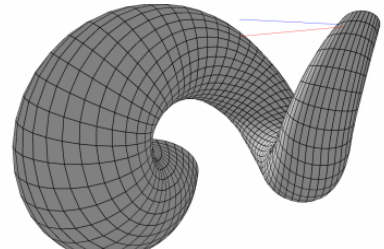
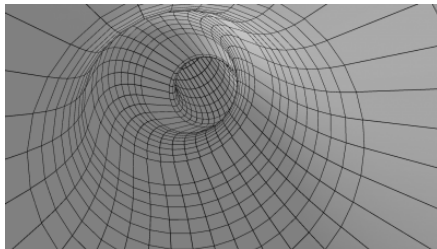
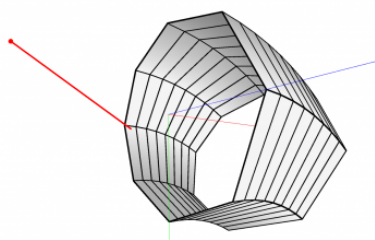


## Infra graphique

Dérive dans les images semi-graphiques. Avant le graphisme «hi-res». Journal : [infra-graphique](http://infra-graphique)

## Quaternion

Exploration des quaternions et de la modélisation procedurale avec Processing





Les sketches Processing ci-dessous dépendent de façon importante sur deux librairies non officielles:

- **QueasyCam** (modifié), pour la navigation dans l'espace en 3D → <https://github.com/gweltou/queasycam/tree/master/distribution/queasycam-6/download/>
- **LibAvatar**, pour l'intégration des classes de LibGDX dans Processing → <https://github.com/gweltou/Processing-libAvatar/blob/2.0/distribution/libAvatar-3/download/libAvatar.zip>

Vous pouvez naviguer dans l'espace 3D avec les touches ZQSDA et E. Affichage en mode filaire avec W.

### iteration1.pde

```
import queasycam.*;
import com.badlogic.gdx.math.*;
import nervoussystem.obj.*;

QueasyCam cam;

static final Vector3 xAxis = new Vector3(1.0, 0.0, 0.0);
float rootSize = 8;
int numSeg = 128;

Segment root = new Segment(null, 10, new Quaternion());

public void setup() {
  fullscreen(P3D);

  cam = new QueasyCam(this, 1, 9999);
  cam.key_forward = 'o';
  cam.key_left = 'k';
  cam.key_backward = 'l';
  cam.key_right = 'm';
  cam.key_up = 'i';
  cam.key_down = 'p';

  sphereDetail(16);

  Segment c1 = root.branch(rootSize, new Quaternion().setEulerAngles(0, 0, -100));
  Segment c2 = root.branch(rootSize, new Quaternion().setEulerAngles(120, 0, -100));
  Segment c3 = root.branch(rootSize, new Quaternion().setEulerAngles(240, 0, -100));
  for (int i=0; i<numSeg; i++) {
    c1 = c1.branch(rootSize * pow(1.0-i/(20.0*numSeg), i), new Quaternion());
    c2 = c2.branch(rootSize * pow(1.0-i/(20.0*numSeg), i), new Quaternion());
    c3 = c3.branch(rootSize * pow(1.0-i/(20.0*numSeg), i), new Quaternion());
  }

  root.update();
}

public void draw() {
  checkKeys();

  background(255);
  lights();

  noStroke();
  translate(width/2, height/2);

  sphere(50);

  root.draw();
}

void checkKeys() {
  if (keyPressed == false)
    return;

  float step = 0.1;
  Quaternion rotation = new Quaternion();
  if (key == 'a') {
    rotation.setEulerAngles(-step, 0.0, 0.0);
  }
}
```

```

    if (key == 'z') {
        rotation.setEulerAngles(step, 0.0, 0.0);
    }
    if (key == 'q') {
        rotation.setEulerAngles(0.0, -step, 0.0);
    }
    if (key == 's') {
        rotation.setEulerAngles(0.0, step, 0.0);
    }
    if (key == 'w') {
        rotation.setEulerAngles(0.0, 0.0, -step);
    }
    if (key == 'x') {
        rotation.setEulerAngles(0.0, 0.0, step);
    }
}

for (Segment seg : root.children) {
    while (seg.hasChildren()) {
        seg.localRot.mul(rotation).nor();
        seg = seg.children.get(0);
    }
    seg.localRot.mul(rotation).nor();
}

root.update();
}

/*****
**      class Segment      **
*****/

public class Segment {
    static final int faces = 32;
    static final float l2b = 10.0; // Length to base ratio

    protected Segment parent = null;
    protected Vector3 head = new Vector3();
    protected Vector3 rootWorldPos = null;

    private Quaternion localRot = new Quaternion(); // Rotation from parent Segment
    private Quaternion globalRot = new Quaternion(); // Total rotation in world space
    private float len;
    private float baseRadius;
    private Vector3[] points = new Vector3[faces];
    private Vector3 tmpVec = new Vector3();

    private ArrayList<Segment> children = new ArrayList();

    public Segment(Segment parent, float len, Quaternion rot) {
        this.parent = parent;
        if (parent == null) {
            rootWorldPos = new Vector3();
            globalRot = rot.cpy();
        } else {
            rootWorldPos = parent.rootWorldPos;
        }
        this.localRot = rot.cpy();
        this.len = len;
        baseRadius = len * l2b * 0.5;
    }

    public Segment branch(float len, Quaternion rot) {
        Segment child = new Segment(this, len, rot);
        children.add(child);
        return child;
    }

    public boolean hasChildren() {
        return !children.isEmpty();
    }

    public void draw() {
        // Draw head line
        stroke(0);
        Vector3 up = new Vector3(0, len*0.4, 0);
        globalRot.transform(up);
        if (parent != null)
            line(parent.head.x, parent.head.y, parent.head.z, head.x, head.y, head.z);
        else
            line(0.0, 0.0, 0.0, head.x, head.y, head.z);

        // Draw UP line
        stroke(255, 0, 0);
        line(head.x, head.y, head.z, head.x + up.x, head.y + up.y, head.z + up.z);

        noStroke();
        if (hasChildren())
            drawSegment();
        else
            drawTip();

        for (Segment child : children)

```

```

    child.draw();
}

private void drawSegment() {
beginShape(QUAD_STRIP);
for (int i=0; i<faces+1; i++) {
    if (parent == null) {
        Quaternion rot = new Quaternion();
        rot.setFromAxisRad(xAxis, i * TWO_PI / faces);
        rot.mulLeft(globalRot);
        rot.transform(tmpVec);
        tmpVec.set(len, baseRadius, 0.0);
    } else {
        tmpVec.set(parent.points[i%faces]);
    }
    vertex(tmpVec.x, tmpVec.y, tmpVec.z);
    tmpVec.set(points[i%faces]);
    vertex(tmpVec.x, tmpVec.y, tmpVec.z);
}
endShape();
}

private void drawTip() {
// Draw a capped tip if this segment has no children
beginShape(TRIANGLE_FAN);
vertex(head.x, head.y, head.z);
for (int i=0; i<faces+1; i++) {
    if (parent == null) {
        Quaternion rot = new Quaternion();
        rot.setFromAxisRad(xAxis, i * TWO_PI / faces);
        rot.mulLeft(globalRot);
        rot.transform(tmpVec);
        tmpVec.set(len, baseRadius, 0.0);
    } else {
        tmpVec.set(parent.points[i%faces]);
    }
}
endShape();
}

public void update() {
Vector3 pos = rootWorldPos.cpy();
globalRot.set(localRot);
if (parent != null) {
    pos.add(parent.head);
    globalRot.mulLeft(parent.globalRot).nor();
}
head.set(len, 0.0, 0.0); // Going right by default
globalRot.transform(head);
head.add(pos);

float angle = 0.0;
Quaternion rot = new Quaternion();
for (int i=0; i<faces; i++) {
    rot.setFromAxisRad(xAxis, angle);
    rot.mulLeft(globalRot);
    tmpVec.set(len, baseRadius, 0.0);
    rot.transform(tmpVec);
    points[i] = tmpVec.cpy().add(pos);
    angle += TWO_PI / faces;
}

for (Segment child : children)
    child.update();
}
}

```

## iteration2.pde

```

import queasycam.*;
import com.badlogic.gdx.math.*;
import nervoussystem.obj.*;
import processing.pdf.*;

static final Vector3 xAxis = new Vector3(1.0, 0.0, 0.0);
static final Vector3 yAxis = new Vector3(0.0, 1.0, 0.0);
static final Vector3 zAxis = new Vector3(0.0, 0.0, 1.0);

QueasyCam cam;

boolean wireframe = false;
boolean record = false;

ArrayList<Drawable> objects = new ArrayList();

public void setup() {
    fullScreen(P3D);
    //size(800, 600, P3D);

```

```

cam = new QueasyCam(this, 1, 9999);
cam.key_forward = 'z';
cam.key_left = 'q';
cam.key_backward = 's';
cam.key_right = 'd';
cam.key_up = 'e';
cam.key_down = 'a';

Pipe pipe = new Pipe(
    new Vector3(0, 0, 0), new Quaternion().setEulerAngles(10, 0, 40),
    10, 32);
objects.add(pipe);
float size = 20;
for (int i=0; i<8; i++) {
    pipe.changeSize(size);
    size += 10;
    pipe.addBend(90, 0.0, 45.0);
}
}

public void draw() {
    background(255);
    lights();

    strokeWeight(1);
    stroke(255, 0, 0);
    line(0, 0, 0, 100, 0, 0);
    stroke(0, 255, 0);
    line(0, 0, 0, 0, 100, 0);
    stroke(0, 0, 255);
    line(0, 0, 0, 0, 0, 100);

    if (wireframe)
        stroke(0);
    else
        noStroke();
    strokeWeight(2);

    if (record) {
        beginRaw(PDF, "output.pdf");
        noFill();
    }

    for (Drawable o : objects)
        o.draw();

    if (record) {
        record = false;
        endRaw();
    }
}

void keyPressed() {
    if (key == 'w')
        wireframe = !wireframe;

    if (key == 'p')
        record = true;
}

public interface Drawable {
    public void draw();
    public void update();
}

public interface Chainable extends Drawable {
    public Vector3 getOutPos();
    public Quaternion getOutOrientation();
}

/*****
**      class Pipe      **
*****/

public class Pipe implements Drawable {
    private Vector3 pos;
    private Quaternion orientation;
    private float radius;
    private float nextRadius;
    private int faces;
    private ArrayList<Chainable> objects = new ArrayList();
    private Vector3 currentPos;
    private Quaternion currentOrientation;

    public Pipe(Vector3 pos, Quaternion orientation, float radius, int faces) {
        this.pos = pos;
        this.orientation = orientation;
        this.radius = radius;
        this.nextRadius = radius;
        this.faces = faces;
    }
}

```

```

    currentPos = this.pos.cpy();
    currentOrientation = orientation.cpy();
}

public void changeSize(float next) {
    this.nextRadius = next;
}

private void add(Chainable object) {
    objects.add(object);
    currentPos = object.getOutPos();
    currentOrientation = object.getOutOrientation();
    radius = nextRadius;
}

public void addTube(float len) {
    addTube(len, 0.0);
}

public void addTube(float len, float twist) {
    Tube tube = new Tube(
        currentPos, currentOrientation,
        len, radius, nextRadius, twist, 1, faces
    );
    add(tube);
}

public void addBend(float angleBendDeg) {
    addBend(angleBendDeg, 0.0, 0.0);
}

public void addBend(float angleBendDeg, float angleRotDeg) {
    addBend(angleBendDeg, angleRotDeg, 0.0);
}

public void addBend(float angleBendDeg, float angleRotDeg, float twist) {
    int rings = 8;
    float radInt = 50;
    currentOrientation.mul(new Quaternion().setEulerAngles(0, angleRotDeg, 0));
    Bend bend = new Bend(
        currentPos, currentOrientation,
        radius, nextRadius,
        radians(angleBendDeg), radInt, twist,
        rings, faces
    );
    add(bend);
}

public void update() {
    for (Chainable o : objects)
        o.update();
}

public void draw() {
    for (Chainable o : objects) {
        o.draw();
    }

    Vector3 head = currentOrientation.transform(new Vector3(32, 0, 0));
    head.add(currentPos);
    line(currentPos.x, currentPos.y, currentPos.z, head.x, head.y, head.z);
}
}

```

```

/*****
**      class Tube      **
*****/

```

```

public class Tube implements Drawable, Chainable {
    private Vector3 pos;
    private Quaternion orientation;
    private float len;
    private float radiusIn;
    private float radiusOut;
    private float twist;
    private int rings;
    private int faces;
    private Vector3[] points;
    private Vector3 tmpVec = new Vector3();
    private Vector3 outPos = new Vector3();
    private Quaternion outOrientation = new Quaternion();

    public Tube(
        Vector3 pos,
        Quaternion orientation,
        float len,
        float radiusIn,
        float radiusOut,
        float twist, // In degrees
        int rings, int faces
    ) {
        this.pos = pos.cpy();
        this.orientation = orientation.cpy();
    }
}

```

```

    this.len = len;
    this.radiusIn = radiusIn;
    this.radiusOut = radiusOut;
    this.twist = radians(twist);
    this.rings = rings;
    this.faces = faces;
    points = new Vector3[faces * (rings+1)];
    update();
}

Vector3 getOutPos() {
    return outPos.cpy();
}

Quaternion getOutOrientation() {
    return outOrientation.cpy();
}

public void update() {
    Quaternion rot = new Quaternion();
    int pointIdx = 0;
    for (int s=0; s<rings+1; s++) {
        float angle = s * twist/rings;
        for (int i=0; i<faces; i++) {
            tmpVec.set(s * len/rings, map(s, 0, rings, radiusIn, radiusOut), 0.0);
            rot.setFromAxisRad(xAxis, angle).mulLeft(orientation);
            rot.transform(tmpVec);
            points[pointIdx++] = tmpVec.cpy().add(pos);
            angle += TWO_PI / faces;
        }
    }
    outOrientation.set(orientation);
    outOrientation.mul(new Quaternion().setFromAxisRad(xAxis, twist));
    outPos.set(len, 0.0, 0.0);
    outOrientation.transform(outPos);
    outPos.add(pos);
}

public void draw() {
    for (int s=0; s<rings; s++) {
        beginShape(QUAD_STRIP);
        for (int i=0; i<faces+1; i++) {
            tmpVec.set(points[s * faces + i%faces]);
            vertex(tmpVec.x, tmpVec.y, tmpVec.z);
            tmpVec.set(points[(s+1) * faces + i%faces]);
            vertex(tmpVec.x, tmpVec.y, tmpVec.z);
        }
        endShape();
    }
}
}

/*****
**      class Bend      **
*****/

public class Bend implements Drawable, Chainable {
    private Vector3 pos;
    private Quaternion orientation;
    private float radiusIn;
    private float radiusOut;
    private float bendAngle;
    private float radInt;
    private float twist;
    private int rings;
    private int faces;
    private Vector3[] points;
    private Vector3 tmpVec = new Vector3();
    private Vector3 outPos = new Vector3();
    private Quaternion outOrientation = new Quaternion();

    public Bend(
        Vector3 pos,
        Quaternion orientation,
        float radiusIn,
        float radiusOut,
        float bendAngle, // In radians
        float radInt, // Internal radius
        float twist,
        int rings,
        int faces
    ) {
        this.pos = pos.cpy();
        this.orientation = orientation.cpy();
        this.radiusIn = radiusIn;
        this.radiusOut = radiusOut;
        this.bendAngle = bendAngle;
        this.radInt = radInt;
        this.twist = radians(twist);
        this.rings = rings;
        this.faces = faces;
        points = new Vector3[faces * (rings+1)];
    }
}

```

```

    update();
}

Vector3 getOutPos() {
    return outPos.cpy();
}

Quaternion getOutOrientation() {
    return outOrientation.cpy();
}

public void update() {
    int pointIdx = 0;
    Quaternion segRot = new Quaternion();
    Quaternion rot = new Quaternion();
    Vector3 bendOffset = new Vector3(0.0, radInt + radiusIn, 0.0);
    orientation.transform(bendOffset);
    float angleSeg = 0.0;
    for (int s=0; s<rings+1; s++) {
        segRot.setFromAxisRad(zAxis, angleSeg);
        segRot.mulLeft(orientation);
        float tubeRadius = map(s, 0, rings, radiusIn, radiusOut);
        Vector3 segOffset = new Vector3(0.0, radInt + tubeRadius, 0.0);
        segRot.transform(segOffset);
        angleSeg += bendAngle / rings;
        float angle = s * twist/rings;
        for (int i=0; i<faces; i++) {
            tmpVec.set(0.0, tubeRadius, 0.0);
            rot.setFromAxisRad(xAxis, angle);
            rot.mulLeft(segRot);
            rot.transform(tmpVec);
            points[pointIdx++] = tmpVec.cpy().sub(segOffset).add(bendOffset).add(pos);
            angle += TWO_PI / faces;
        }
    }

    outPos.set(0, -radiusOut - radInt, 0);
    outOrientation.set(orientation);
    outOrientation.mul(new Quaternion().setFromAxisRad(zAxis, bendAngle));
    outOrientation.transform(outPos);
    outOrientation.mul(new Quaternion().setFromAxisRad(xAxis, twist));
    tmpVec.set(0.0, radInt + radiusIn, 0.0);
    orientation.transform(tmpVec);
    outPos.add(tmpVec).add(pos);
}

public void draw() {
    for (Vector3 p : points) {
        point(p.x, p.y, p.z);
    }

    for (int s=0; s<rings; s++) {
        beginShape(QUAD_STRIP);
        for (int i=0; i<faces+1; i++) {
            tmpVec.set(points[s * faces + i%faces]);
            vertex(tmpVec.x, tmpVec.y, tmpVec.z);
            tmpVec.set(points[(s+1) * faces + i%faces]);
            vertex(tmpVec.x, tmpVec.y, tmpVec.z);
        }
        endShape();
    }
}
}

```

Article extrait de : <https://lesporteslogiques.net/wiki/> - **WIKI Les Portes Logiques**

Adresse : [https://lesporteslogiques.net/wiki/recherche/residence\\_infra/start?rev=1731842830](https://lesporteslogiques.net/wiki/recherche/residence_infra/start?rev=1731842830)

Article mis à jour : **2024/11/17 12:27**