

# 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/>

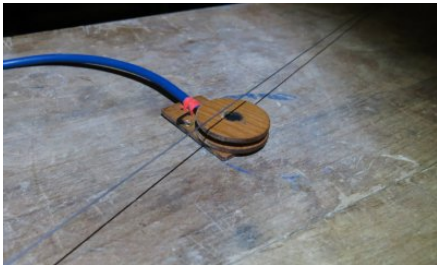
<https://multitude.exsitu.xyz/v/map/19255da86d5b11f61>

## 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



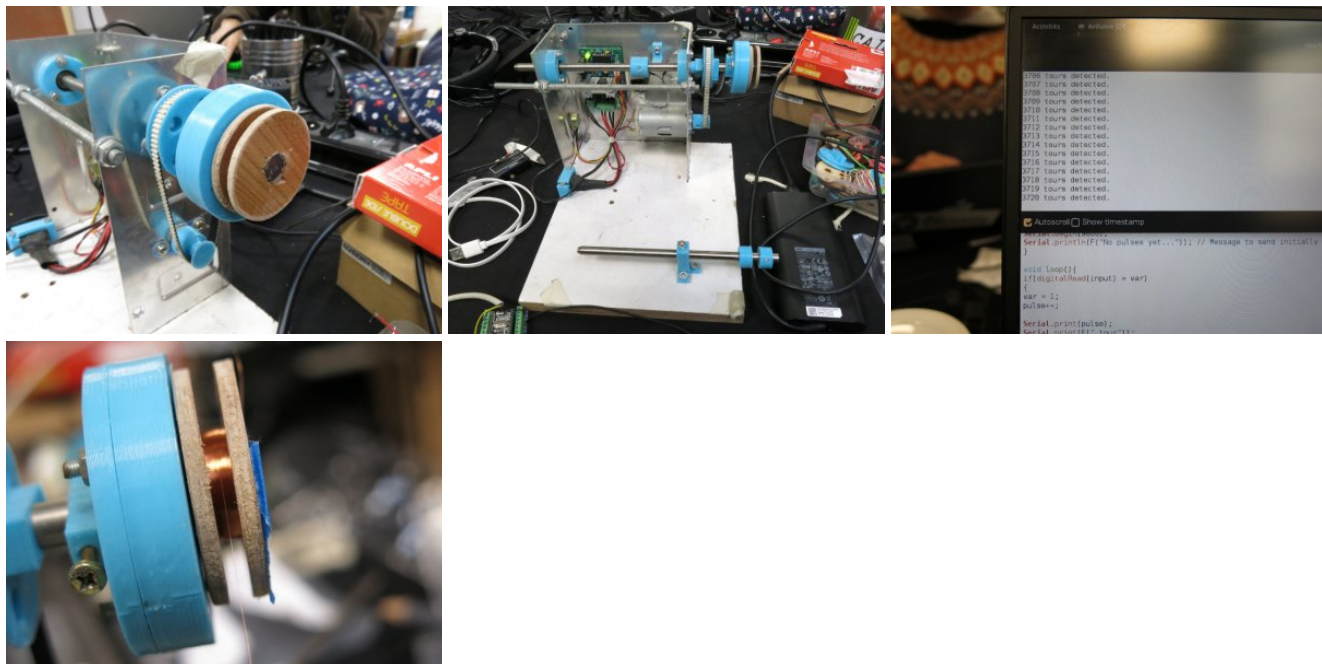
Profiter de ces beaux jours d'automne pour se chauffer au néons et ressortir la petite [bobineuse](#) pour créer un mirco

## 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

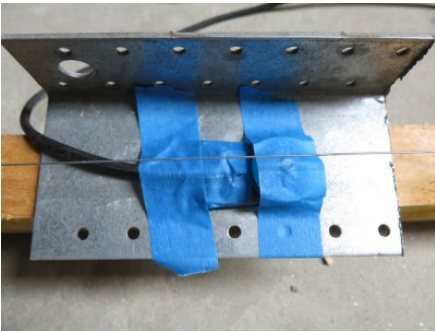
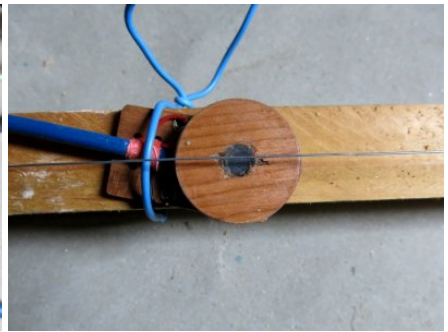
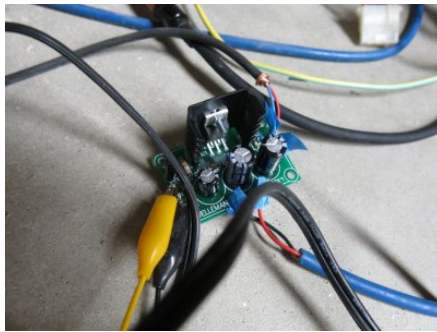
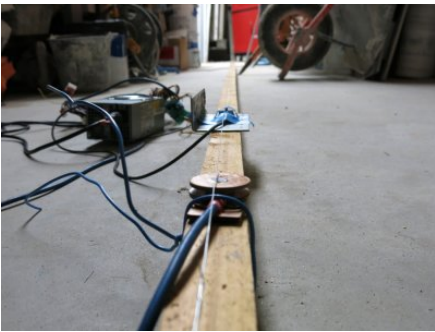
- Pour donner à l'ensemble un peu d'homogénéité et surtout protéger la bobine le tout est laissé trempé dans de la paraffine jusqu'à temps qu'il n'y ai plus de petites bulles



## essai infrabassique avec retour d'informations



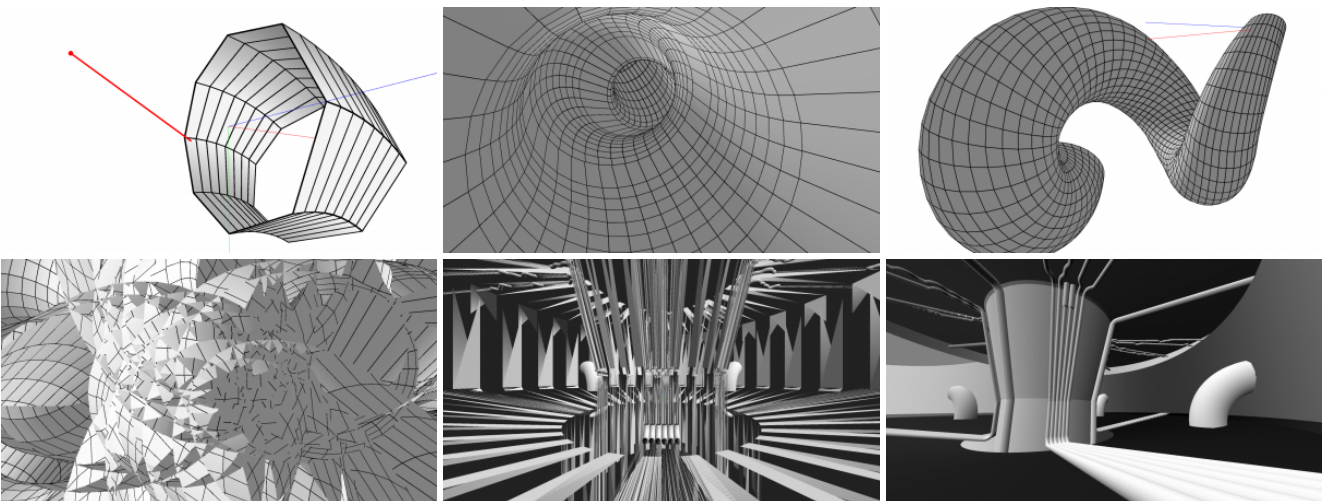
- Ça fonctionne plutôt bien au niveau des infras
- Ajout d'un second micro (caché sous le scotch bleu)
- Câblage du gros micro et du petit avec un ampli mono 7W pour créer un feedback de résonances



## Infra graphique

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

## Quaternion



## 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 : <http://www.lesporteslogiques.net/wiki/> - **WIKI Les Portes Logiques**

Adresse : [http://www.lesporteslogiques.net/wiki/recherche/residence\\_infra/start?rev=1731840127](http://www.lesporteslogiques.net/wiki/recherche/residence_infra/start?rev=1731840127)

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