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STRUCTURAL OPTIMIZATION OF ROTOR BLADES WITH STRAIGHT AND SWEPT TIPS SUBJECT TO AEROELASTIC CONSTRAINTS

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LIST OF SYMBOLS

b	Blade semichord
C_T	Thrust coefficient
$\vec{D}$	Vector of design variables
$f(\vec{D})$	Objective function
$\nabla F(\vec{D})$	Gradient of objective function or behavior constraints
$\vec{g}(\vec{D})$	Vector of behavior constraints
h_s	Height of the single cell cross section
$[H(\vec{D}_0)]$	Hessian of objective function or behavior constraints
I_b	Mass moment of inertia of the blade in flapping
J	Mass polar moment of inertia of the rotor
ℓ	Length of the elastic portion of the blade
t_1	Thickness of the cross section
V_{zpk}	Peak-to-peak value of the 4/rev vertical hub shears, nondimensionalized through division by $2\Omega^2 I_b/\ell$
x_A	Offset between the elastic axis and the aerodynamic center, positive for aerodynamic center ahead of the elastic axis
x_I	Offset between the elastic axis and the center of gravity, positive for center of gravity ahead of the elastic axis
x_1	Distance between leading edge and internal wall in double cell cross section
x_2	Chordwise length of the cross section
γ	Blade Lock number
ζ_k	Real part of hover stability eigenvalue for the k-th mode
Λ	Tip sweep angle, positive for backward sweep
μ	Advance ratio
σ	Rotor solidity
Ω	Rotor angular velocity

1. INTRODUCTION AND PROBLEM STATEMENT

One of the most cost effective solutions to the problem of vibration in rotorcraft is to design rotor blades with an inherently low vibration level. This can be accomplished by aeroelastic tailoring the blade, using structural optimization. This implies that the blade mass and stiffness distributions and its geometry are determined in such a manner that the vibration levels at the rotor hub are minimized. Using this approach vibrations are reduced directly at their source, i.e., the rotor.

A thorough review of the literature concerning the use of optimum design techniques in dynamic problems, and particularly in helicopter rotor blade dynamic design, is presented in ref. (1). A more recent survey has been presented by Friedmann (ref. 2). These reviews reveal the existence of a very limited amount of work devoted to the structural optimization of rotor blades for vibration reduction.

In another recent survey Miura (ref. 3) states that it is not unreasonable to pursue design optimization in areas, such as helicopter vibration reduction, in which reliable prediction capabilities do not exist yet. Better optimization technology can be developed and implemented in highly modular computer codes so that new, improved analysis codes can be easily incorporated as they become available, and the optimization program can work with the best predictive capability available at any particular time.

When the mass and stiffness distributions of the blade are changed to reduce the vibration levels it is very important to be sure that no degradation of the aeroelastic stability occurs. This is even more important when tip sweep is added as a design variable because of its powerful influence on both blade response and stability (ref. 4). Prudence mandates the introduction of aeroelastic stability constraints in the optimum design process. This complicates the design problem because a fully coupled aeroelastic stability and response analysis has to be combined with the structural optimization program. Only a few studies having this capability are available (refs. 1,5,6). In refs. (1,5,6) the objective was the minimization of the 4/rev oscillatory vertical hub shears at an advance ratio μ = 0.3. The aeroelastic stability constraints required that the fundamental frequencies in flap, lag, and torsion fall between pre-assigned upper and lower bounds.

In a study by Peters *et al.* (ref. 7) two different objective functions were used to minimize blade weight in one case, and the discrepancy between desired and actual natural frequencies of the blade. A simplified forced response analysis leads the authors to conclude that the objective functions used in the study are "adequate" for vibration reduction purposes, but no comprehensive aeroelastic analysis is performed, and no stability constraints are imposed on the design.

Davis and Weller (ref. 8) used structural optimization techniques to solve four different dynamic problems, namely: (a) maximization of the in-plane structural damping of a bearingless rotor with elastomeric dampers; (b) placement of blade natural frequencies; (c) minimization of the vibratory hub shears using a simplified rotor aerodynamic model; and (d) minimization of certain rotor vibration indices. The rotor analysis codes were directly coupled to the optimization codes. No aeroelastic stability constraints were considered.

More recent work has also addressed the minimum weight design of rotor blades with frequency constraints (ref. 9) as well as the vibration reduction problem in forward flight by using optimally placed tuning masses (ref. 10) without enforcing aeroelastic response analysis to obtain the vibratory loads. Such studies are useful since they contribute towards the overall understanding of the problem; however, the possibility exists that such an approach may not produce reliable designs. A very detailed combined experimental and theoretical study (ref. 11), aimed at experimental verification of helicopter blade designs optimized for vibration reduction, indicated the need for using the dynamic loading on the blade, obtained from the aeroelastic response, in the optimization process.

A serious problem encountered in the direct coupling of a comprehensive aeroelastic stability and response code with an optimization, or nonlinear mathematical programming code is the very large computation effort required for the solution. This problem can be alleviated by constructing an *approximate*, computationally easier to solve, optimization problem (ref. 12). The approximate problems converge to the solution of the original, exact optimization problems.

One typical method of constructing the approximate problem is to expand the objective function and the behavior constraints in first or second order Taylor series in terms of the design variables, and in the neighborhood of the current design (ref. 12). This method originated in the field of static structural analysis, in which the gradient information required to construct the Taylor series expansions can be obtained at a fraction of the cost of one analysis, through implicit differentiation (ref. 13). This is difficult to achieve in helicopter aeroelastic optimization, and the gradient information has to be constructed using expensive-to-compute finite difference approximations. References (1,5,6) utilized an expensive approach

based on finite differences for generating approximations to the objective function and aeroelastic constraints. The generation of the approximate problem was cumbersome and had to be carried out in an interactive manner, during the optimization process. It is also possible to construct approximate problems using derivatives, or the sensitivity of the objective function. This approach was successfully used in a recent, comprehensive optimization study by Lim and Chopra (ref. 14).

This paper has three main objectives:

1. To describe a new formulation of the structural optimization problem for a helicopter rotor blade in forward flight. The objective is the minimization of the n/rev vertical hub shears. The behavior constraints express mathematically the requirements that the blade be aeroelastically stable, that its natural frequencies fall between preassigned upper and lower bounds, and that the autorotation performance not be degraded during the aeroelastic tailoring process. A new formulation of the approximate problem allows increases in efficiency, in the complete solution of the optimum design problem, of at least one order of magnitude, compared with existing procedures.

2. To present results obtained by letting the *tip sweep angle* be one of the design variables in the optimization procedure. Tip sweep has a powerful influence on the dynamic behavior the blade, and when included in the aeroelastic tailoring process, can lead to further reductions in blade vibration levels.

3. To describe some ongoing work being carried out at UCLA on the structural optimization of rotor blades with straight and swept tips.

Finally it should be noted that a considerable amount of additional results pertaining to the first two objectives of this paper can be found in refs. (15)-(18).

2. AEROELASTIC STABILITY AND RESPONSE ANALYSIS

This section describes briefly the aeroelastic stability and response analysis and the procedure used to calculate the vertical hub shears, that is, the analysis portion of the optimum design process. The equations of motion of the straight blade are similar to those derived in ref. (19). The modeling of the swept tip is described in ref. (4). The equations describe the coupled flap-lag-torsional motion of a flexible, homogeneous, isotropic blade, modeled as a Bernoulli-Euler beam undergoing small strains and moderate deflections. Geometrically nonlinear terms are present in the structural, inertia, and aerodynamic operators, due to nonlinear beam kinematics. The inertia loads are obtained using D'Alembert's principle. Quasi-steady strip theory, with uniform inflow, is used to derive the aerodynamic loads. Stall and compressibility effects are not included. In the modeling of the swept tip the independence principle is assumed to apply, that is, the aerodynamic loads depend only on the component of the flow contained in the plane of the cross section, and radial flow effects are neglected (ref. 4).

The spatial dependence of the partial differential equations of motion of the blade is eliminated by using a Galerkin method of weighted residuals (ref. 19). This results in a finite element discretization. Cubic interpolation polynomials are used for the modeling of flap and lag bending, quadratic interpolation polynomials for the modeling of torsion. The resulting finite elements have a total of 11 degrees of freedom: displacement and slope at each end of the element, for flap and

lag bending, rotation at each end of the element and at a mid-element node, for torsion. The axial degree of freedom is eliminated by making the assumption that the blade is inextensional. The partial differential equations of motion of the blade are thus transformed into a set of nonlinear, coupled, ordinary differential equations with periodic coefficients. A modal coordinate transformation is performed to reduce the number of degrees of freedom. Six rotating coupled blade normal modes are used to perform the modal coordinate transformation. The coupled modes are calculated for a root pitch angle equal to the collective pitch.

In forward flight, the equilibrium position of the blade is time dependent, and is obtained by solving a sequence of linear, periodic response problems, using quasilinearization. The stability of the system is determined using Floquet theory. A special, implicit formulation of quasilinearization (ref. 20) which reduces considerably the implementation effort is used. The algebraic expressions that define the aerodynamic loads are not expanded explicitly. They are coded separately in the computer program and combined numerically during the solution procedure. Quasilinearization is a Newton-Raphson type procedure, and the derivative matrices that are required by the algorithm are computed using finite different approximations.

The overall helicopter trim procedure used in this study is a propulsive trim procedure identical to that used in ref. (21).

The calculation of the hub loads, consisting of forces and moments, is performed using the direct force integration method. The response of the blade is obtained from the aeroelastic response calculation code; thus the hub loads are obtained from a spanwise integration of the inertia and aerodynamic loads distributed along the blade. Details on the hub loads calculations can be found in refs. 15-18.

3. FORMULATION OF THE OPTIMUM DESIGN PROBLEM

The optimization problem is cast in nonlinear mathematical programming form. Thus the objective is to minimize a function $f(\vec{D})$ of a vector $\vec{D}$ of design variables, subject to a certain number of constraints $\vec{g}(\vec{D}) \leq 0$:

$$\text{minimize } f(\vec{D}) \tag{1}$$

subject to:

$$\vec{g}(\vec{D}) \leq 0 \tag{2}$$

To reduce the computational requirements, the computer program performing the aeroelastic analysis is not connected directly to the optimization program. Instead, the optimization is conducted on an *approximate problem*, which reproduces the characteristics of the actual problem in a neighborhood of the current design, and which is continuously updated as the optimization progresses.

An effective method of building an approximate problem is to expand the objective function and the behavior constraints in Taylor series in terms of the design variables (ref. 9):

$$F(\vec{D}) \approx F(\vec{D}_0) + \nabla F(\vec{D}_0)\delta\vec{D} + \frac{1}{2}\,\delta\vec{D}^T[H(\vec{D}_0)]\delta\vec{D} \tag{3}$$

where $F(\vec{D})$ is taken to be any objective or constraint function, $\vec{D}_0$ is the current design, and $\nabla F(\vec{D}_0)$ and $[H(\vec{D}_0)]$ are respectively the gradient and the Hessian matrix at the current design. The Hessian matrix is the matrix of the second partial derivatives of the objective function with respect to the design variables. The perturbation vector $\delta\vec{D}$ is defined as

$$\delta\vec{D} = \vec{D} - \vec{D}_0 \tag{4}$$

The most expensive function to evaluate is the objective function. The cost of one evaluation of the objective function is two orders of magnitude higher than the total cost of evaluating the behavior constraints. No analytic expressions for the gradients are available for the objective function, and finite difference approximations are required for the construction of the derivative information in Eq. (3). Therefore, if n design variables are used in the optimization, n additional aeroelastic analyses are required to compute the gradient, and an additional n(n+1)/2 for the calculation of the Hessian, making the cost of building the Taylor series approximation to the objective function extremely high. For this reason an alternative approximation technique, introduced by Vanderplaats [22,23], was used in this study.

This alternative technique is based on the idea of approximating the gradient and the Hessian in Eq. (3), not by using small finite difference steps, but by using whatever design information is available at the time. Eq. (3) can be rewritten, in expanded form, as (refs. 22,23).

$$\begin{aligned}\Delta F = {} & \nabla F_1\delta D_1 + \nabla F_2\delta D_2 + \ldots + \nabla F_n\delta D_n + \tfrac{1}{2}(H_{11}\delta D_1^2 + H_{22}\delta D_2^2 + \ldots + H_{nn}\delta D_n^2) \\ & + H_{12}\delta D_1\delta D_2 + H_{13}\delta D_1\delta D_3 + \ldots + H_{1n}\delta D_1\delta D_n \\ & + H_{23}\delta D_2\delta D_3 + \ldots + H_{n-1,n}\delta D_{n-1}\delta D_n\end{aligned} \tag{5}$$

In which

$$\Delta F = F(\vec{D}) - F(\vec{D}_0) = F - F_0 \tag{6}$$

and

$$\nabla F_i = \nabla F_i(\vec{D}_0) \; ; \quad H_{ij} = H_{ij}(\vec{D}_0) \tag{7}$$

Assume that a baseline design $\vec{D}_0$ has been analyzed to give F_0, and that other designs $\vec{D}_1, \vec{D}_2, \ldots, \vec{D}_k$ have been previously analyzed, to provide $F_1, F_2, \ldots F_k$. Let

$$\delta\vec{D}_i = \vec{D}_i - \vec{D}_0 \qquad i = 1,2,\ldots,k \tag{8}$$

and

$$\Delta F_i = F_i - F_0 \qquad i = 1,2,\ldots,k \tag{9}$$

If k designs are available, Eq. (5) can be written k times. The unknowns of the resulting linear system are ∇F_1, $\nabla F_2,\ldots,\nabla_k$, and H_{11}, $H_{12},\ldots,H_{nn}$. If the designs are linearly independent, the system ℓ equations (5) will provide all the coefficients required for the quadratic polynomial approximation Eq. (3). If all the designs are very closely spaced, the solution to the gradient and Hessian matrix at $\vec{D}_0$. Equation (3) will then represent a truncated Taylor series expansion of F, valid in a neighborhood of $\vec{D}_0$. If the designs are dispersed in the design space, Eq. (3) will simply be a quadratic polynomial approximation, defined over a wider region of the design space.

An important characteristic of this technique is that the system of equations (5) can be written with less than ℓ equations. If at least n + 1 designs are available, the solution of the system will provide a linear portion of the approximation, Eq. (3). An approximate optimization can be conducted, based on this linear approximation. The resulting optimum is then analyzed precisely and provides an additional design: a system of n + 2 equations (5) can then be written. Its solution will provide a new approximation, Eq. (5), with all the linear terms plus one pair of quadratic terms of the symmetric Hessian matrix. The process can then be repeated, with each new approximate optimum providing an additional design point to increase the number of terms in the quadratic approximation to objective function and behavior constraints.

One iteration of the optimum design process thus consists of the following six steps:

1. Calculation of the blade properties, including natural frequencies and mode shapes;
2. Aeroelastic analysis in hover;
3. Aeroelastic analysis in forward flight, including calculation of hub loads;
4. Calculation of objective function and behavior constraints;
5. Calculation of a new approximation (linear or incomplete quadratic) to objective function and behavior constraints;
6. Solution of the approximate constrained optimization problem, using the feasible direction code CONMIN (refs. 24,25) to obtain a new, improved blade design.

The process is terminated when a feasible, optimum design has been reached, or arbitrarily, when the improvement in the design is considered "adequate".

The first n + 1 iterations of the procedure are not true optimization iterations because steps 5 and 6 above are not performed. In fact, these initial iterations are used to generate a sufficient number of designs to build at least an initial linear approximation to objective function and behavior constraints.

Side constraints are placed on the design variables to prevent them from reaching impractical values which violate practical, physical constraints. Thus all the thicknesses and distances are assumed to be nonnegative numbers.

Three different types of *behavior constraints* are placed on the design.

1. *Frequency placement constraints.* The fundamental frequencies in flap, lag and torsion are required to fall between preassigned upper and lower bounds. if ω is one of the three frequencies, and ω_l and ω_u are the preassigned lower and upper bound respectively, the frequency placement constraint is expressed mathematically in the form:

$$g(\vec{D}) = \frac{\omega^2}{\omega_U^2} - 1 \leq 0 \tag{10}$$

$$g(\vec{D}) = 1 - \frac{\omega^2}{\omega_L^2} \leq 0 \tag{11}$$

Equations (10) and (11), written for each of the three fundamental frequencies of the blade, provide a total of six behavior constraints. Furthermore, the frequencies are also constrained so as to be sufficiently removed from the n/rev frequencies.

2. *Aeroelastic stability constraints.* The blade is required to be aeroelastically stable in hover. No constraints are placed on the stability in forward flight because all the blade configurations considered in this optimization study are soft-in-plane blade configurations, and the effect of forward flight is usually stabilizing for this type of blades (ref. 21). The aeroelastic stability constraints are expressed mathematically in the form:

$$g(\vec{D}) = \zeta_k \leq 0 \qquad k = 1,2,\ldots,m \tag{12}$$

If m modes are used to perform the modal coordinate transformation in the solution of the equations of motion, there are m constraint equations like Eq. (12), where the quantify ζ_k is the real part of the hover stability eigenvalue for the k-th mode. As indicated in the results section, in some cases more stringent aeroelastic constraints were also imposed.

3. *Autorotation constraints.* The autorotation constraint expresses the requirement that possible mass redistributions produced in the optimization process do not degrade the autorotation properties of the rotor. The most convenient autorotation constraint is one which restricts variations of the polar mass moment of inertia of the rotor (ref. 26, pp. 346-364). Therefore, the autorotation constraint is expressed mathematically in the form:

$$g(\vec{D}) = 1 - \frac{J}{0.9J_0} \leq 0 \tag{13}$$

The constraint equation (13) requires that the mass polar moment of inertia J of the rotor maintain, during the optimization, at least 90% of its initial value J_0.

Therefore, *a total of thirteen behavior constraint equations* are placed on the design variables.

4. RESULTS

The basic blade configuration considered in this study is a soft-in-plane hingeless blade, shown in Figure 1, which is part of a four bladed rotor. The uncoupled fundamental lag, flap, and torsion frequencies, for zero tip sweep, are 0.732/rev, 1.125/rev, and 3.17/rev respectively. The Lock number is $\gamma = 5.5$, the thrust coefficient $C_T = 0.005$, and the rotor solidity $\sigma = 0.07$. For the swept tip configurations, the outermost 10% of the blade is swept. The blade precone angle β_p, the

root offset e_1, the offset x_A between the elastic axis and the aerodynamic center, and the offset x_I between the elastic axis and the cross sectional center of gravity are all set to zero, unless specified otherwise. The modal coordinate transformation is based on the six lowest frequency, rotating, coupled modes of the blade. In all cases the six modes were one torsion, two lag, and three flap modes. The blades were modeled using 5 finite elements, with nodes at 0%, 22.5%, 45%, 67.5%, 90% and 100% of the span. Selected results are presented here. Numerous additional results can be found in refs. (15)-(18).

Two types of cross sections are considered in this study, namely a single cell, rectangular cross section, and a double cell cross section. Both cross sections are shown in Figure 2. Up to five, and up to nine independent design parameters can be specified for the single cell and the double cell cross section respectively (ref. 16). In this study the cross sectional design parameters are linked in such a way as to reduce the number of independent design parameters to two, for both the single and the double cell cross sections. The first independent design variable is the thickness t_1 of all the elements of which both cross sections are composed. The second independent design variable is the chordwise width x_2 for both cross sections. In the single cell cross section the ratio between the width x_2 and the height h_s is kept constant, with $x_2/h_s = 4.5$. In the double cell cross section the internal wall is placed halfway between the leading edge and the rear wall, so that $x_1 = x_2/2$. The outside wall of the double cell cross section has the shape of a NACA 0012 airfoil. The properties of both cross sections are presented in ref. (16).

As a preliminary to the optimization studies, the effect of tip sweep on the peak-to-peak values of the 4/rev vertical hub shears was investigated.

Figure 3 shows the peak-to-peak value V_{zpk} of the vertical hub shears as a function of the tip sweep angle Λ, for four different values of the advance ratio μ, for the soft-in-plane blade configuration. Figure 3 shows that tip sweep may or may not be beneficial for the soft-in-plane configuration, depending on the advance ratio and the tip sweep angle. At an advance ratio $\mu = 0.3$ the oscillatory loads rapidly increase with tip sweep. At $\mu = 0.4$, instead, tip sweep has a beneficial effect. Based on the results of this preliminary investigation, the advance ratio at which the 4/rev vertical hub shears are minimized was set at $\mu = 0.4$.

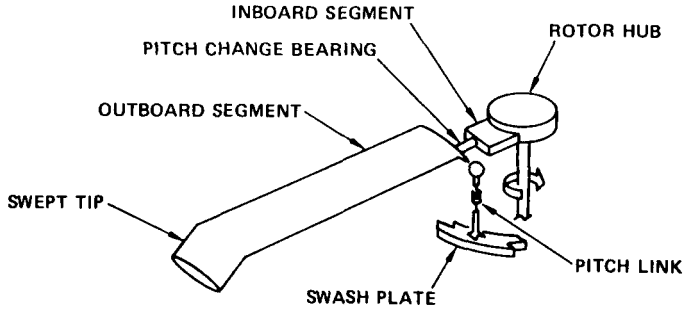

Figure 1: Swept tip hingeless rotor blade model.

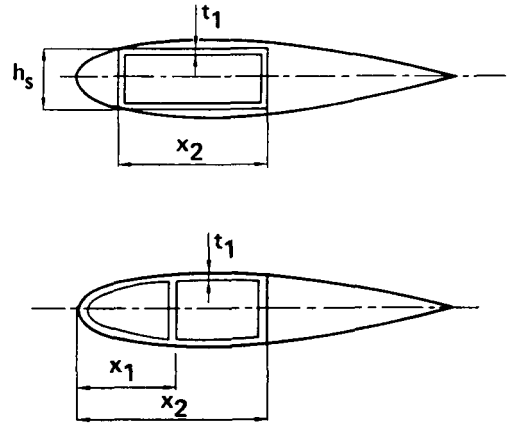

Figure 2: Single and double cell cross sections.

Three optimization studies were conducted using the general procedure outlined in the previous section, namely:

1. Optimization of a completely straight blade, having a two-cell cross section. The objective function is the peak-to-peak value of the 4/rev vertical hub shears at an advance ratio $\mu = 0.4$.

   The design variables are defined at three distinct cross sections of the blade: the root section, the tip section, and the cross section at the 67.5% span, *for a total of six independent design variables.* The 67.5% station, at which two design variables are defined, is the junction section between the third and the fourth finite element. The blade properties are assumed to vary linearly between two consecutive stations at which the design variables are specified.

2. Optimization of a completely straight blade, having a single cell cross section. As in the previous case, the objective function is the peak-to-peak value of the 4/rev vertical hub shears at an advance ratio $\mu = 0.4$.

   As in Case 1, the design variables are defined at three distinct cross sections of the blade: the root section, the tip section, and the cross section at the 67.5% span, *for a total of six independent design variables.*

   The cross section is rectangular, therefore doubly symmetric. Because leading edge masses have not been used in this particular example, the center of gravity and the aerodynamic center are located on the elastic axis of the blade - which is taken to be coincident with the pitch axis. Therefore the associated offsets are equal to zero.

3. Straight blade with a swept tip. The objective function is the peak-to-peak value of the 4/rev vertical hub shears divided by the thrust coefficient C_T, at

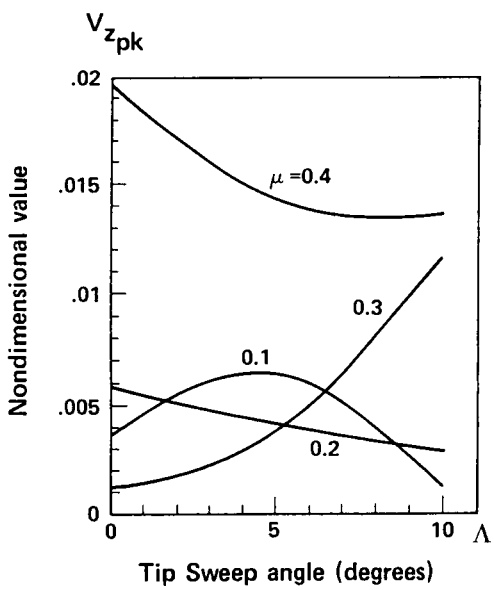

Figure 3: Effect of tip sweep on the peak-to-peak value of the vertical hub shears, soft-in-plane blade configuration.

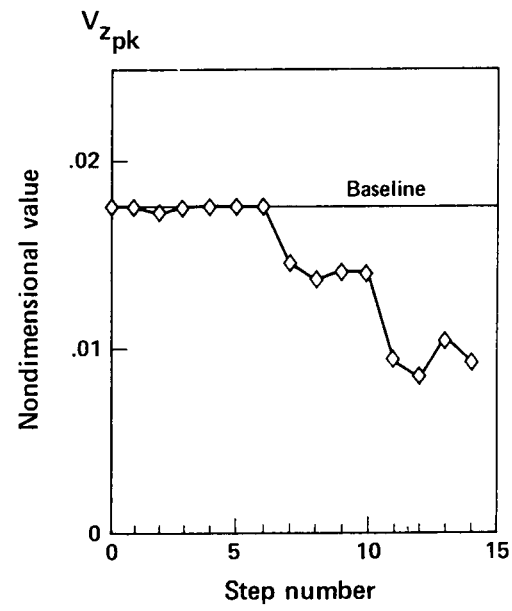

Figure 4: Case 1 - Iteration history of the objective function.

an advance ratio $\mu = 0.4$. This particular choice of objective function is an attempt to compensate for the inaccuracy of the trim program, which neglects the torsional deformation of the blade and thus overestimates the thrust that the rotor is actually capable of developing.

The outermost 10% of the blade is swept, with the sweep angle being a design variable of the optimization procedure. The cross section is rectangular, and therefore the offsets x_I and x_A are equal to zero. The cross sectional design variables are designed as in Case 2. Therefore *a total of seven design variables* is used in this case.

The initial blade configuration, for all three cases, is the baseline soft-in-plane configuration.

Optimization Case 1

The iteration history of the objective function for case 1 is shown in Fig. 4. It should be noted that for all three optimization cases, design n is defined as the design produced at the end of the optimization step n. Step 0 and the first six steps are not true optimization steps: they are required to obtain enough information to build linear approximations to the objective function and behavior constraints. Step 0 is the analysis of the baseline design. In steps 1 through 6 each of the six design variables is perturbed, one at a time. Because the perturbations were relatively small - 1% of the baseline value - the linear approximations obtained at the end of step 6 can be considered as gradients calculated using forward flight difference approximations.

Step 7 is the first true optimization step and consists of the solution of a linear optimization problem. Move limits were placed on the design variables, which could not change by more than 25% of the baseline value. The optimization continues for three additional steps (8-10). Each new proposed design is analyzed precisely and is used to improve the polynomial approximations to objective function and behavior constraints. The diagonal of the Hessian matrix is built first, as more function evaluations become available. (The term "Hessian" is used in this section with the general meaning of "matrix coefficients of the quadratic terms at the approximation"). Figure 4 shows that, after reaching a minimum at step 8, the objective function slightly oscillates.

As the constrained optimum of the approximate problem, the approximate flap damping constraint for the first flap mode was active. In most helicopter blades the first flap mode tends to be highly damped, and a precise analysis of the proposed design showed that this indeed was the case, and that the precise first flap stability constraint was satisfied. The constraint was therefore reformulated as

$$\zeta_{F1} - 0.3 < 0 \qquad (14)$$

The subsequent optimization steps were performed with this new form of the constraint, which prevents the *approximate* constraint from becoming critical. Two more steps (11 and 12) are performed with the relaxed flap constraint. The design of step 12 is a local, unconstrained minimum of the approximate problem. The corresponding blade is such that a reduction of 54.3% is achieved in the objective function, compared with the baseline configuration. The design suggested by the optimizer for step 13 is practically the same as that for step 12. A different design was instead arbitrarily selected for step 13. This design was "close" to that of step 12, and was selected for the only purpose of adding one design to the design data base and to try to improve the accuracy of the approximations in the neighborhood of design 12 -

with the design of step 13 the full diagonal of the Hessian can be built. Step 14 is the last optimization step, and it produces a value of the objective function that is slightly higher than the minimum of step 12. The optimization was arbitrarily stopped at this point. All the designs generated during the optimization were feasible. Iteration histories on the design variables are presented in refs. (15)-(17), and for conciseness are not repeated here.

Optimization Case 2

The iteration history of the *objective function* for case 2 is shown in Fig. 5. Steps 0 through 6 are not true optimization steps. These steps are required to generate enough designs to construct at least linear approximations to objective function and behavior constraints. The design at step 0 is the baseline blade design. The designs analyzed in steps 1 through 6 are obtained by changing one design variable at the time. Since the change in each variable was equal to 10% of its baseline value, the resulting linear approximations to objective functions and behavior constraints cannot be strictly considered as gradients.

The first true optimization step is step 7, which consists of a linear, constrained optimization problem. A reduction of 37.6% is achieved, compared with the baseline design. In the next step the objective function increases slightly. Because this behavior is somewhat similar to the one observed in case 1, the optimization was arbitrarily concluded as this point, and restarted *with a new set of behavior constraints.*

The aeroelastic stability constraints used in case 1, and up to this point in case 2, consist of requiring that the blade be aeroelastically stable in hover. It is prudent to require that the optimization process do not degrade too much the stability margin of the baseline design. The optimization was thus restarted from step 9 with these more stringent behavior constraints. The aeroelastic constraints of Eq. (12) are reformulated as

$$g(D) = 1 - \frac{\zeta_k}{0.95\zeta_{kB}} \leq 0 \qquad k = 1,2,\ldots,m \tag{15}$$

Equation (15) expresses the requirement that the loss of stability of a given mode should not exceed 5% of the baseline value ζ_{kB}.

The optimization is not restarted with a new calculation of an initial linear approximation. Rather, the previous designs are reused to provide the initial approximation for the new case. While designs 0 through 8 were all feasible with respect to the old set of behavior constraints, some of these designs are now feasible with respect to the tightened aeroelastic stability constraints. In particular, design 8, which becomes the initial design for the second phase of this optimization, is infeasible.

The first design produced by the optimizer with the new set of constraints is feasible with respect to the *approximate* behavior constraints. When this design is analyzed precisely, it proves to be infeasible with respect to the *exact* behavior constraints. The successive design (step 10) is feasible with respect to both the approximate and the exact behavior constraints. The next design (step 11) is again feasible with respect to the approximate, but not the exact behavior constraints. In steps 9 through 11 the objective function is constantly at a value higher than the baseline value and does not show any signs of convergence to the optimum. In other

words, the optimizer does not seem to be able to produce a feasible design that improves on the baseline design, which satisfies the new constraint equations, Eq. (15).

The apparently erratic behavior of the objective function required a reconsideration of the optimization strategy which, starting from step 14, was modified, and tighter move limits were enforced, in a selective manner. This modified approach finally yields design 16 which represents a reduction in peak-to-peak value of the 4/rev vertical hub shears to 16.6% compared to the baseline value. Thus the imposition of aeroelastic constraints reduces the gains in the objective function by more than 50%.

Optimization Case 3

Figure 6 shows the iteration history of the objective function for case 3, which is the peak-to-peak value of the 4/rev vertical hub shears divided by the thrust coefficient C_T. The tightened aeroelastic constraints of Eq. (15) are enforced.

Design 0 is the baseline soft-in-plane straight blade configuration. The first seven steps are not true optimization steps. As in cases 1 and 2, they provide enough precise values of the objective function and behavior constraints to build at least a linear approximation of objective and constraints. In the designs 1 through 7 each of the seven design variables is perturbed, one at a time. Design 7 is the only swept blade design. Designs 0 through 6 are straight blade designs and are identical to the corresponding designs of case 2. Thus these designs are not reanalyzed to derive the results of Figure 3, and need not be recalculated.

Thus the optimization process of case 3 begins without the need for any precise analyses, in the sense that the eight precise analyses required to start the procedure were already available from previous parts of this study and could be directly reutilized. The ability to make use of previously analyzed designs, even if not very

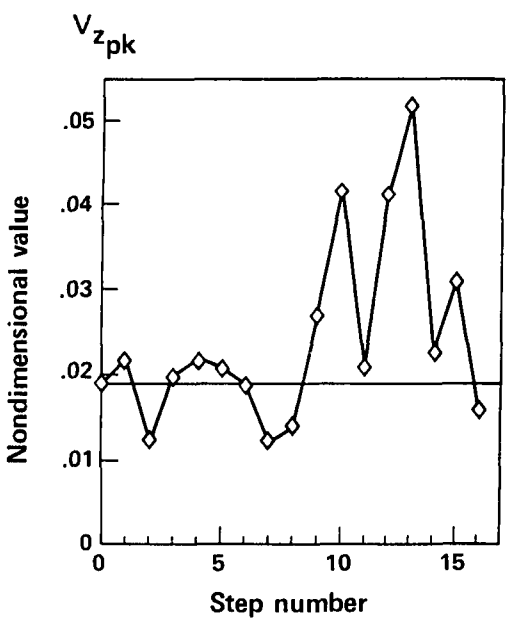

Figure 5: Case 2 - Iteration history of the objective function.

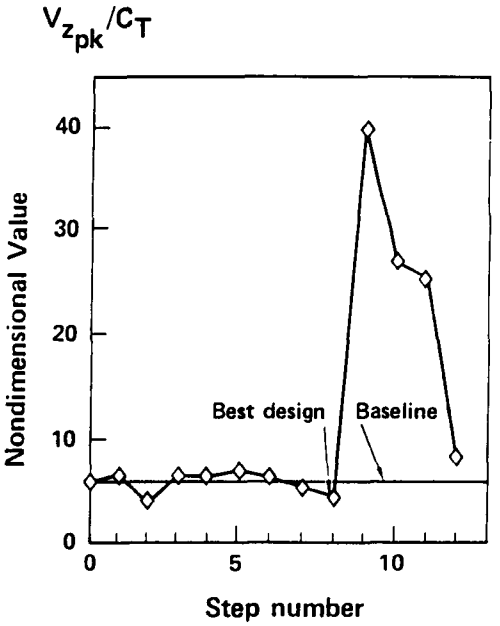

Figure 6: Case 3 - Iteration history of the objective function.

close to the expected optimum in the design space of the current problem, is one of the most important features of the optimization algorithm used in this study.

The first true optimization step, step 8, produces a design with a reduction of 27.2% of the objective function with respect to the baseline straight blade. This also corresponds to a reduction of 14.5% with respect to the best swept tip design obtained without applying formal optimization techniques, that is design 7. When analyzed precisely, the design proves feasible, with no constraints active. Compared with the final result of case 2, in which the blade is straight, the use of tip sweep as an additional design variable allows a further reduction of the objective function of almost 10%.

The next two steps (9 and 10) produce much higher values of the objective function. Starting from step 11 the "modified" strategy previously outlined is employed. The next two steps (11 and 12) provide considerable reductions of the objective function, but the best design is still design 8. The optimization is arbitrarily stopped at this point, both for cost reasons, and because the design appears to converge towards design 8.

The iteration histories of the thickness t_1, the chordwise extension of the spar, and the tip sweep angle Λ are shown in Figs. 7, 8, and 9 , respectively. The tip sweep angle corresponding to the best design is $\Lambda = 9°$.

Next, it is relevant to comment on the computational requirements encountered in this study. The results were obtained on an IBM 3090-200 computer. Each precise aeroelastic analysis required three to four iterations of quasilinearization (ref. 16). Each iteration of quasilinearization required 80-110 CPU seconds for a straight blade and 140-180 CPU seconds for a swept tip blade. Because a variable step, Adams-Bashforth technique was used to integrate the equations of motion (ref. 4), the exact CPU time required to complete an iteration of quasilinearization was problem dependent.

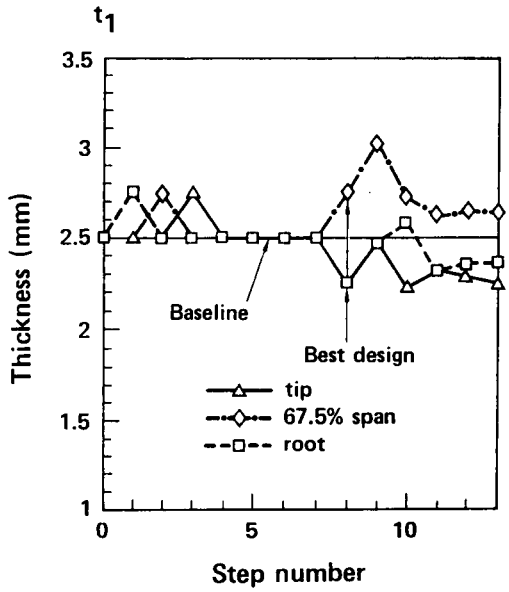

Figure 7: Case 3 - Iteration history of thickness t_1.

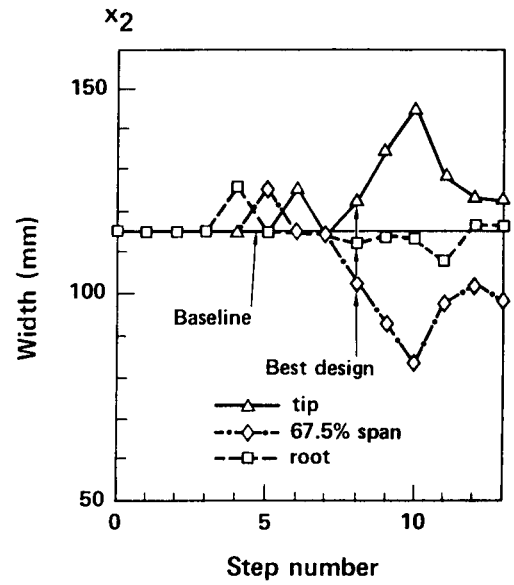

Figure 8: Case 3 - Iteration history of chordwise width x_2.

The remaining portions of a complete optimization step, namely the calculation of the cross sectional properties of the blade, the calculation of the vertical hub shears from the aeroelastic response of the blade, the derivation of the polynomial approximations to objective function and behavior constraints, and the solution of the approximate constrained optimization problem, required an average *total* 1-2 CPU seconds.

5. ONGOING EXTENSION OF THE RESEARCH ON ROTOR BLADE OPTIMIZATION WITH AEROELASTIC CONSTRAINTS

Ongoing research at UCLA is aimed at extending the work described in the previous sections in several directions. First, more efficient means of generating the approximate problem are being considered using intermediate design variables representing cross-sectional stiffness properties. Next, the structural model of the blade is being improved by replacing the isotropic structural blade model by a model which is capable of modeling a composite rotor blade with multicell cross sections. A more accurate representation of the unsteady aerodynamic loads is also being pursued. Finally alternative choices for the objective functions are also being considered so that the multidisciplinary nature of our current optimization capability is enhanced.

6. CONCLUDING REMARKS

The main conclusions obtained in the present study are summarized below. Their application to the structural optimization of a helicopter blade should be limited by the assumptions used in obtaining the numerical results presented in this study.

1. The optimum design procedure described in this study is very efficient, and can produce improved designs with a very limited number of precise analyses. The

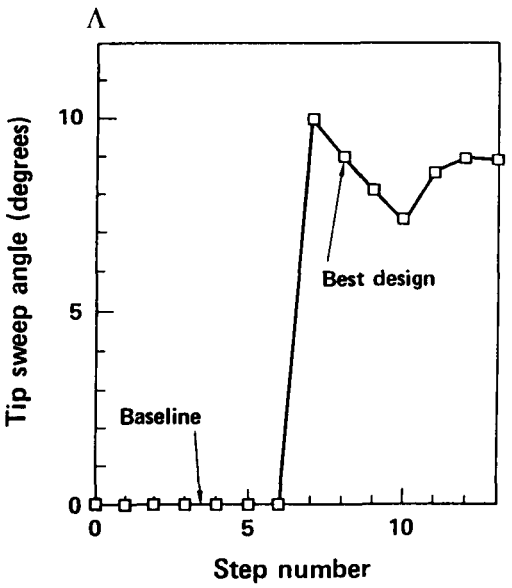

Figure 9: Iteration history of tip sweep angle Λ.

method of constructing the approximate problem is such that previously conducted aeroelastic analyses can be reused in a new optimization problem. For example, if an optimization study is preceded by a parametric study in which the effect of various combinations of blade design parameters is examined, all the aeroelastic analyses performed for the parametric study can be reutilized in the optimization study. This is not possible when the approximate problem is built from Taylor series expansions.

2. The results of the optimization are quite sensitive to the aeroelastic stability margins required of the blade. In the optimization of case 2, changing the aeroleastic stability constraints from simply requiring that the blade be stable in hover, to requiring that the stability margins be maintained during the course of the optimization, reduced the gains in n/rev vibration levels by more than 50%.

3. The introduction of tip sweep can reduce the n/rev vertical hub shears beyond the level that can be obtained by just modifying the mass and stiffness distributions of the blade.

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