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SEQUENTIAL OPTIMIZATION AND RELIABILITY ASSESSMENT METHOD FOR EFFICIENT PROBABILISTIC DESIGN

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ABSTRACT

Probabilistic optimization design offers tools for making reliable decisions with the consideration of uncertainty associated with design variables/parameters and simulation models. In a probabilistic design, such as reliability-based design and robust design, the design feasibility is formulated probabilistically such that the probability of the constraint satisfaction (reliability) exceeds the desired limit. The reliability assessment for probabilistic constraints often involves an iterative procedure; therefore, two loops are involved in a probabilistic optimization. Due to the double-loop procedure, the computational demand is extremely high.

To improve the efficiency of a probabilistic design, a novel method – sequential optimization and reliability assessment (SORA) is developed in this paper. The SORA method employs a single-loop strategy where a serial of cycles of optimization and reliability assessment is employed. In each cycle optimization and reliability assessment are decoupled from each other; no reliability assessment is required within optimization and the reliability assessment is only conducted after the optimization. The key concept of the proposed method is to shift the boundaries of violated deterministic constraints (with low reliability) to the feasible direction based on the reliability information obtained in the previous cycle. Hence the design is quickly improved from cycle to cycle and the computational efficiency is improved significantly. Two engineering applications, the reliability-based design for vehicle crashworthiness of side impact and the integrated reliability and robust design of a speed reducer, are presented to demonstrate the effectiveness of the SORA method.

1. INTRODUCTION

Traditional optimization designs are pushed to the limits of system failure boundaries, leaving very little or no room for accommodating uncertainties in engineering design. Consequently, deterministic optimization designs obtained without any consideration of uncertainties may be sensitive to the variation of system (leading to quality loss), risky (high likelihood of undesired events or low constraint satisfaction), or conservative and therefore uneconomic if deterministic safety factors are larger than required. It is therefore important to incorporate uncertainty in engineering design optimization and develop computational techniques that enable engineers to make efficient and reliable decisions.

Probabilistic design methods have been developed and have been applied in engineering design. The typical probabilistic design methods include reliability-based design (Wu and Wang, 1996; Carter, 1997; Grandhi and Wang, 1998) and robust design (Chen, et al, 1996; Du and Chen, 2000a). Reliability-based design emphasizes high reliability of a design by ensuring the probabilistic constraint satisfaction at desired levels, while robust design focuses on making the design inert to the variations of system input through optimizing mean performance of the system and minimizing its variance simultaneously. One important task of a probabilistic design is uncertainty analysis, through which we understand how much the impact of the uncertainty associated with the system input is on the system output by identifying the probabilistic characteristics of system output. We then perform synthesis (optimization) under uncertainty to achieve our design objective by managing and mitigating the effects of uncertainty on system output (system performance) (Du and Chen, 2000b).

In spite of the benefits of probabilistic design, one of the most challenging issues for implementing probabilistic design is associated with the intensive computational demand of uncertainty analysis. To capture the probabilistic characteristics of system performance at a design point, we need to perform a number of deterministic analyses in the vicinity of the nominal point, either using simulation approach (for instance, Monte Carlo simulation) or other probabilistic analysis methods (such as reliability analysis). Many researches have been concentrating on developing practical means to make probabilistic design computationally feasible for complex engineering problems.

Our focus in this study is to develop an efficient probabilistic design approach to facilitate design optimizations that involve probabilistic constraints. Reliability-based design is such type of probabilistic optimization problems (Reddy, et al., 1993; Wang, et al., 1995; Chen and Hasselman, 1997; Tu; et al., 1999) in which design feasibility is formulated as reliability constraints (or the probability of constraint satisfaction). The conventional approach for solving a probabilistic optimization problem is to employ a double-loop strategy in which the analysis and the synthesis are nested in such a way that the synthesis loop (outer loop) performs the uncertainty analysis (inner loop for reliability assessment) iteratively for meeting the probabilistic objective and constraints. As the double-loop strategy may be computationally infeasible, various techniques have been developed to improve its efficiency. These techniques can be classified into two categories: one is through improving the efficiency of uncertainty analysis methods, for example, the methods of Fast Probability Integration (Wu, 1994) and Two-Point Adaptive Nonlinear Approximations (Grandhi and Wang, 1998); the other is through modifying the formulation of probabilistic constraints, for example, the performance measure approach (Tu and Choi, 1999). A comprehensive review of various feasibility modeling approaches for design under uncertainty is provided in Du and Chen (2000b).

Even though the improved uncertainty analysis techniques and modifications of problem formulation have lead to improved efficiency of probabilistic optimization, the improvement is quite limited due to the nature of the double loop strategy. Recent years have seen preliminary studies on a new type of method - single loop method (Chen and Hasselman, 1997; Wu, et al., 2001). In Wu's work, a method of "approximately equivalent deterministic constraints" is developed, which creates a link between a probabilistic design and a safety-factor based design. In Chen's work, the reliability constraints are formulated as deterministic constraints that approximate the condition of the Most Probable Point (MPP) (Hasofer and Lind, 1974), a concept used for reliability assessment. Although the single loop strategy appears promising as no nested synthesis and uncertainty analysis loops are involved because the probabilistic constraints are approximated by the equivalent deterministic constraints, these methods are relatively new and will require further investigations and verifications that can illustrate their improvement over the double-loop strategy by testing various applications.

In this paper, we present a new probabilistic design method, Sequential Optimization and Reliability Assessment (SORA) that we believe can significantly improve the efficiency of probabilistic optimization. Our method employs a single loop strategy which decouples optimization synthesis and uncertainty analysis. As an integral part of the proposed strategy, we employ the formulation of performance measure for the reliability constraints along with an efficient inverse MPP search algorithm. In this paper, we will first review a few commonly used strategies of probabilistic design in Section 2. The review will lay the foundation for our proposed method, SORA, introduced in Section 3. In Section 4 two engineering examples are used to illustrate the effectiveness of the proposed method. Section 5 is the closure, which highlights the effectiveness of the proposed method and provides discussions on its applicability under different circumstances.

2. PROBABILISTIC OPTIMIZATION STRATEGIES

In this section, we present two commonly used probabilistic design strategies, which lay the foundation for our proposed method. These two strategies are also used for the purpose of comparison when verifying our proposed method.

2.1 Double-Loop Strategy with Probabilistic Formulation

A typical model of a probabilistic design is given by:

Minimize: $f(\mathbf{d}, \mathbf{X}, \mathbf{P})$

Design Variable $DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\}$ (1)

Subject to: $\text{Prob}\{g_i(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0\} \geq R_i$, i=1~m,

where f is an objective function, d is the vector of deterministic design variables, X is the vector of random design variables, P is the vector of random design parameters, $g_i(\mathbf{d}, \mathbf{X}, \mathbf{P})$ (i=1~m) are constraint functions, R_i are desired probabilities of constraint satisfaction, and m is the number of constraints. The design variables are **d** and the means ($\boldsymbol{\mu}_x$) of the random design variables **X**. Note that the following rules of symbols are used to differentiate the representation of random variables, deterministic variables, and vectors. A capital letter is used for a random variable, a lower case letter for a deterministic variable or a realization of a random variable, and a bold letter is used for a vector. For example, X stands for a random variable and x for a deterministic variable or a realization of random variable X; **X** denotes a vector of random variables while **x** denotes a vector of deterministic variables.

In the above probabilistic design model, the design feasibility is formulated as the probability (Prob) of constraint satisfaction $g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0$ bigger than or equal to a desired probability R. As shown in Fig. 1, the probability of $g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0$ is the area underneath the curve of probability density function (PDF) of g for $g \geq 0$, and this area should be greater than or equal to R.

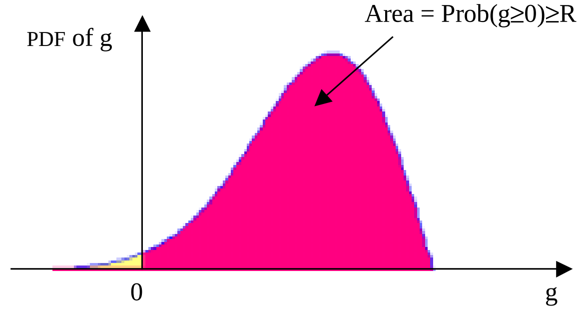

Figure 1. PDF of a Constraint Function g

The probability of constraint satisfaction is also called reliability. Analytically, the reliability is given by the integral

$$\text{Prob}\{g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0\} = \int \cdots \int_{g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0} f_{\mathbf{X},\mathbf{P}}(\mathbf{x}, \mathbf{p}) d\mathbf{x} d\mathbf{p} \, , \quad (2)$$

where $f_{\mathbf{X},\mathbf{P}}(\mathbf{x},\mathbf{p})$ is the joint probability density function of **X** and **P**, and the probability is evaluated by the multidimensional integration over the region $g(\mathbf{d},\mathbf{X},\mathbf{P}) \geq 0$. It is generally difficult or even impossible to perform the multidimensional integration in Eqn. (2). One alternative method to evaluate the integration is Monte Carlo simulation. However, when the reliability is very high (approaching 1.0), the computational effort of Monte Carlo Simulation is prohibitively expensive (Du and Chen, 2000b). Hasofer and Lind (1974) proposed the concept of the Most Probable Point (MPP) in the structural reliability field to approximate the integration.

With the MPP approach, the random variables $(\mathbf{X},\mathbf{P})$ are transformed into an independent and standardized normal space $(\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P})$. The MPP is formally defined in the standardized normal space as the minimum distance point on the constraint boundary $g(\mathbf{d},\mathbf{X},\mathbf{P}) = g(\mathbf{d},\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P}) = 0$ to the origin. The minimum distance β is called reliability index. When the First Order Reliability Method (FORM) (Hasofer and Lind, 1974) is used, the reliability is given by

$$\text{Prob}\{g(\mathbf{d},\mathbf{X},\mathbf{P}) \geq 0\} = \Phi(\beta), \quad (3)$$

where Φ is the standard normal distribution function. Finding the MPP and the reliability index is a minimization problem, which usually involves an iterative searching process. Therefore, the reliability assessment itself is an optimization problem. For details about the MPP based method, refer to Du and Chen (2001a).

When the probability formulation in design model (1) is directly used to solve the problem, the method is called "double-loop method with probability formulation" (DLM_Prob) (Reddy, et al., 1993; Wang, et al., 1995; Tu; et al., 1999). The efficiency of this type of method is usually low since it employs nested optimization loops to first evaluate the reliability of each probabilistic constraint and then to optimize the design objective subject to the reliability requirements.

2.2 Double-Loop Strategy with Percentile Formulation

An equivalent model to (1) is given by (Tu, et al., 1999; Choi and Youn, 2001; Wu, et al, 2001)

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d},\mathbf{X},\mathbf{P}) \\ &\qquad DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \quad (4) \\ &\text{Subject to: } g_i^R(\mathbf{d},\mathbf{X},\mathbf{P}) \geq 0,\ \text{i=1~m}, \end{aligned}$$

where g^R is the R- percentile of $g(\mathbf{d},\mathbf{X},\mathbf{P})$, namely,

$$\text{Prob}\{g(\mathbf{d},\mathbf{X},\mathbf{P}) \geq g^R\} = R \quad (5)$$

Eqn. (5) indicates that the probability of $g_i(\mathbf{d},\mathbf{X},\mathbf{P})$ greater than or equal to the R-percentile g^R is exactly equal to the desired reliability *R*. The concept is demonstrated in Fig. 2. If the shaded area is equal to the desired reliability *R*, then the left ending point g^R on the g axis is called the R-percentile of function g. From Fig. 2 we see that, if $g^R \geq 0$, it indicates that $\text{Prob}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P}) \geq 0\} \geq R$. Therefore, the original constraints that require the reliability assessment are now converted to constraints that evaluate the R-percentile.

The percentile g^R can be evaluated by the inverse MPP method based on FORM, given the desired reliability *R*, the reliability index β is first calculated by

$$\beta = \Phi^{-1}(R) \quad (6)$$

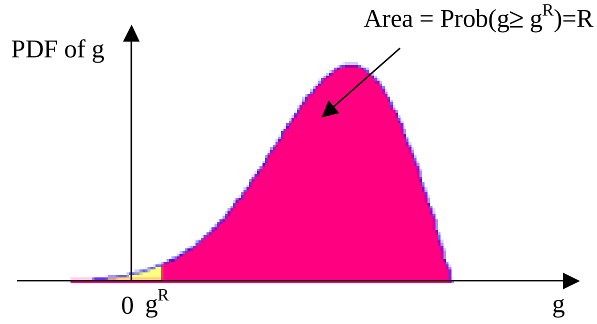

Figure 2. R - Percentile of A Constraint Function

The inverse MPP problem is formulated as shown in the following minimization model,

$$\begin{cases} \text{minimize } g(\mathbf{U}) \\ \text{subject to } (\mathbf{U}^T\mathbf{U})^{1/2} = \beta, \end{cases} \quad (7)$$

where $\mathbf{U} = (\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P})$.

Using an inverse MPP search algorithm, the optimum solution MPP $\mathbf{u}_{MPP}$ can be identified and the R percentile is evaluated by

$$g^R = g(\mathbf{u}_{MPP}) = g(\mathbf{x}_{MPP},\mathbf{p}_{MPP}). \quad (8)$$

To some extent, the evaluation of Eqn. (8) can be viewed as deterministic by substituting the MPP values ($\mathbf{x}_{MPP}$ and $\mathbf{p}_{MPP}$ in the original random space) directly into the *g* function. Since applying the inverse MPP method also involves iterative procedures, we call the method for solving model (4) "the double-loop method with percentile formulation" (DLM_Per). It is also called performance measure approach (PMA) in (Tu, et al., 1999; Choi and Youn, 2001).

To distinguish the type of function evaluations for the probabilistic constraints (Eqns. (3) or (8)) from those for the original constrain functions $g(\mathbf{d},\mathbf{X},\mathbf{P})$, we call the function evaluations for the reliabilities $\text{Prob}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P}) \geq 0\}$ or the R-percentile $g^R = g(\mathbf{u}_{MPP}) = g(\mathbf{x}_{MPP},\mathbf{p}_{MPP})$ "probabilistic function evaluations" and those for the original function $g(\mathbf{d},\mathbf{X},\mathbf{P})$ "the performance function evaluations" or simply "the function evaluations".

For both DLM_Prob and DLM_Per, to fulfill the optimization, the outer loop optimizer calls the objective function and probabilistic constraints repeatedly as illustrated in Fig. 3. Therefore, the total number of function evaluations will be huge. For instance, assume that the outer optimization loop needs 100 probabilistic function evaluations and that there are 10 probabilistic constraints, if each probability evaluation needs 50 function evaluations on average, the total number of function evaluations would be 100×10×50=50,000!

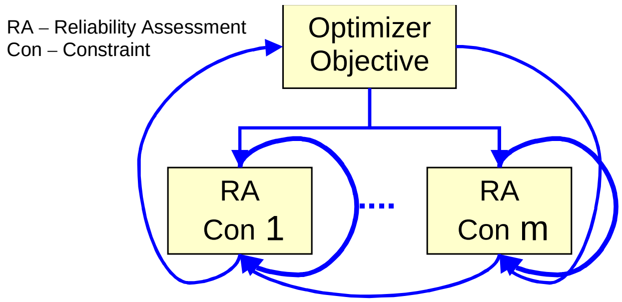

Figure 3. Double Loop Methods

3. Sequential Optimization and Reliability Assessment (SORA) Method

To improve the efficiency of probabilistic optimization, we adopt in this work the strategy of "serial single loops" (Chen and Hasselman, 1997; Wu, et al., 2001) to develop an efficient, sequential optimization and reliability assessment (SORA) method. Our proposed method is different from the existing single loop methods in the way that we establish the equivalent deterministic constraint of the probabilistic constraint. We also employ an efficient inverse MPP search algorithm as an integral part of the proposed procedure.

3.1 The Measures Taken in Developing the SORA Method

In developing the SORA method, several measures have been taken, including evaluating the reliability only at the desired level (R-percentile), using an efficient and robust inverse MPP search algorithm, and employing sequential cycles of optimization and reliability assessment.

(1) Evaluating the reliability only at the desired level (R-percentile)

It is noted that in probabilistic optimization, the closer the reliability $\mathrm{P}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0\}$ is to 1.0, the more computational effort is required. For using the MPP based methods, the higher reliability means larger search region in the standardized normal space to locate the MPP and it is very likely that more function evaluations are required. In probabilistic optimization with multiple constraints, some constraints may never be active and their reliabilities are extremely high (approaching 1). Although these constraints are the least critical, the evaluations of these reliabilities will unfortunately dominate the computational effort in the probabilistic design process if the DLM_Prob strategy (Section 2.1) is employed. The solution to this problem is to perform the reliability assessment only up to the necessary level, represented by the desired reliability *R*.

To this end, we use the percentile formulation for probabilistic constraints with the SORA method. Based on Eqn. (8), the design model (5) of DLM_Per is rewritten as

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d},\boldsymbol{\mu}_{\mathbf{x}}) \\ &DV=\{\mathbf{d},\boldsymbol{\mu}_{\mathbf{x}}\} \qquad (9)\\ &\text{Subject to: } g_i(\mathbf{d},\mathbf{x}_{MPPi},\mathbf{p}_{MPPi})\geq 0,\ \text{i=1\textasciitilde m} \end{aligned}$$

This model establishes the equivalence between a probabilistic optimization and a deterministic optimization since the original constraint functions $g_i(\mathbf{d},\mathbf{x}_{MPPi},\mathbf{p}_{MPPi})$ are used to evaluate design feasibility using the MPPs corresponding to the desired reliabilities Ri. Fig. 4 is used to further explain how a probabilistic constraint is converted to an equivalent deterministic constraint. With two random design variables X_1 and X_2 as an example, we see that the feasible region of a probabilistic design is a reduced region in comparison with a deterministic feasible design. Evaluation of a probabilistic constraint at design solution (μ_{x1}, μ_{x2}) is equivalent to evaluating the deterministic constraint at the MPP point, i.e., $g(\mathbf{d},\mathbf{x}_{MPP},\mathbf{p}_{MPP})$. As shown in Fig. 4, the MPP corresponding to the design point on the probabilistic constraint boundary is exactly on the deterministic constraint boundary. When $g(\mathbf{d},\mathbf{x}_{MPP},\mathbf{p}_{MPP})=0$, it indicates that the shaded area of the probability density function curve of $g(\mathbf{d},\mathbf{X},\mathbf{P})$ is equal to 1-*R* where *R* is the desired reliability. Therefore, to maintain the design feasibility, the MPP of each probabilistic constraint should be within the deterministic feasible region.

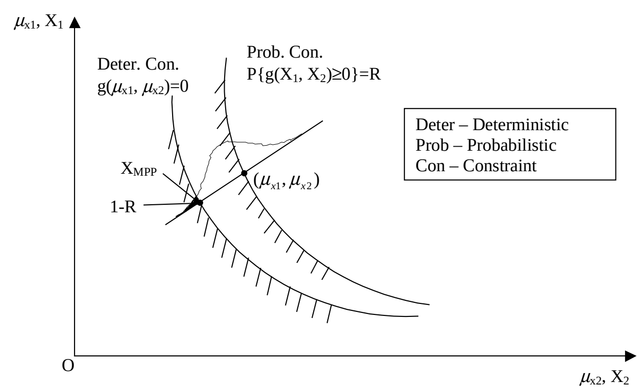

Figure 4. Probabilistic Constraint

(2) Using an efficient and robust inverse MPP search algorithm

In SORA, we employ an efficient MPP based percentile evaluation method (inverse MPP search algorithm) of which principle is introduced in (Du and Chen, 2001a) with more details documented in (Du, 2002). This new MPP search algorithm combines several techniques, such as using the steepest decent direction as the search direction, performing an arc search if no progress is made along the steepest decent direction, and adopting the adaptive step size for numerical derivative evaluation. This search algorithm is considered robust since it is suitable for any continuous constraint functions (including non-concave and non-convex functions) and continuous distributions of uncertainty.

(3) Employing sequential cycles of optimization and reliability assessment

It is noted that in a probabilistic design, most of the computations are used for reliability assessments. Therefore, to improve the overall efficiency of probabilistic optimization we need to reduce the number of reliability assessments as much as possible. The essence is to move the design solution as quickly as possible to its optimum so as to reduce the needs for locating MPPs. To achieve this, SORA employs a serial of cycles of optimization and reliability assessment. Each cycle includes two parts, one part is the (deterministic) optimization and another part is the reliability assessment (see Fig.5). The reliability assessment refers to the evaluation of R-percentile corresponding to a given reliability R. In each cycle, at first we solve an equivalent deterministic optimization problem, which is formulated by the information of the MPPs obtained in the last cycle. Once the design solution is updated, we then perform reliability assessment to identify the new MPPs and to check if all the reliability requirements are satisfied. If not, we use the current MPPs to formulate the constraint for the deterministic optimization in the next cycle in which the constraint boundary will be shifted to the feasible region by changing the locations of design variables. Using this strategy, the reliability of constraints improves progressively and the solution to a probabilistic design can be found within a few cycles, and the need for searching MPPs can be reduced significantly. Detailed flowchart and procedure are provided in Section 3.2.

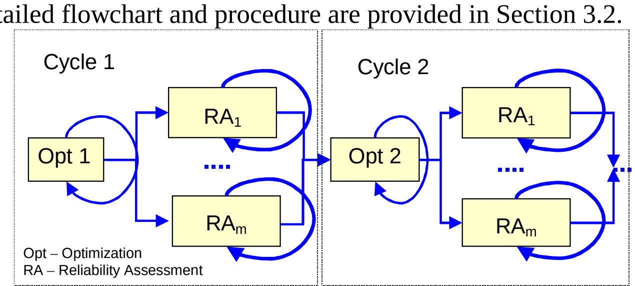

Figure 5. The SORA Method

3.2 SORA Flowchart and Procedure

The flowchart of the SORA method is provided in Fig. 6. For the first cycle, there is no information about the MPPs and they are set as the means of the random design variables and the random parameters. The following optimization in the first cycle is merely a conventional (deterministic) optimization,

$$\begin{aligned}&\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \mathbf{p}_\mathbf{p})\\&DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\}\\&\text{Subject to: } g_i(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p}) \geq 0 \text{ , i=1~m}\end{aligned} \qquad (10)$$

To demonstrate the strategy of separating (deterministic) optimization and reliability assessment while ensuring both segments work together to bring the design solution quickly to a feasible and optimal solution, we use the same illustrative plot (no deterministic design variables d and random parameters P) as shown in Fig. 4 for demonstration. We start our explanation for the first cycle and then extend the same principle to the kth cycle. In the first cycle, after solving model (10) (deterministic optimization), some of the constraints may become active. For an active constraint g, the optimal point $\boldsymbol{\mu}_x^1 = (\mu_{x1}^1, \mu_{x2}^1)$ is on the boundary of the deterministic constraint function $g(\boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p})$. When considering the randomness of X, as seen on the graph (Fig. 7), the actual reliability (probability of constraint being feasible) is around 0.5. Following the deterministic optimization, the reliability assessment is implemented for the deterministic optimum solution $\boldsymbol{\mu}_x^1 = (\mu_{x1}^1, \mu_{x2}^1)$ to locate the MPP that corresponds to the desired R level. As one can expect, the MPP $\mathbf{x}_{MPP}^1$ of constraint $g(\boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p})$ will fall outside (to the left of) the deterministic feasible region. From our discussion in Section 3.1, we know that to ensure the feasibility of a probabilistic constraint, the MPP corresponding to the R percentile should fall within the deterministic feasible region. Therefore, when establishing the equivalent deterministic optimization model in Cycle 2, the constraints should be modified to shift the MPP at least onto the deterministic boundary to help insure the feasibility of the probabilistic constraint. If we use s to denote the shifting vector, the new constraint in the deterministic optimization of the next cycle is formulated as

$$g(\boldsymbol{\mu}_\mathbf{x} - \mathbf{s}) \geq 0 \qquad (11)$$

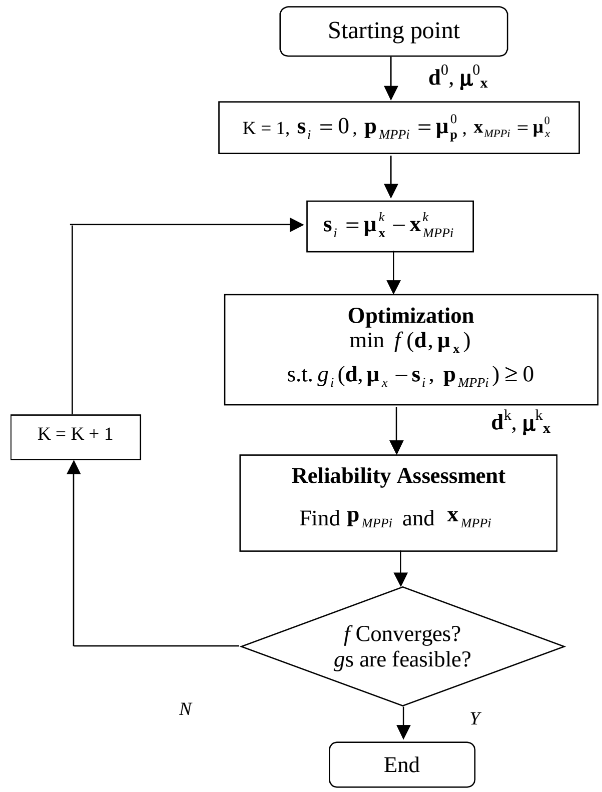

Figure 6. Flowchart of the SORA Method

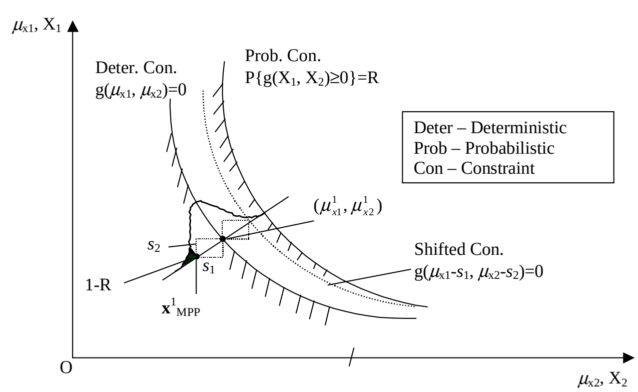

Figure 7. Shifting Constraint Boundary

From Fig. 7, to ensure the MPP onto the deterministic boundary, we derive the shifting vector as

$$\mathbf{s} = (s_1, s_2) = \boldsymbol{\mu}^1_\mathbf{x} - \mathbf{x}_{MPP} = (\mu^1_{x1} - x^1_{1MPP}, \mu^1_{x2} - x^1_{2MPP}). \qquad (12)$$

Correspondingly, Eqn. 11 indicates that the location of the design variables ($\boldsymbol{\mu}_x$) in the deterministic optimization model needs to move further to the boundary of the probabilistic constraint to ensure feasibility under uncertainty. This shifted constraint boundary is shown in Fig. 7 by the dotted curve which is the shifted deterministic constraint curve using the shifting vectors. If there are more than one probabilistic constraints, other constraint boundaries are also shifted towards the feasible region by the distance between the optimal point $\boldsymbol{\mu}_x^1 = (\mu_1^1, \mu_1^2)$ and their own MPPs accordingly. In the optimization of the second cycle, the new constraints form a narrower feasible region in comparison with the one in the first cycle as shown in the following optimization model:

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}) \\ &DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \\ &\text{Subject to: } g(\mathbf{d},\ \mathbf{u}_\mathbf{x} - \mathbf{s}^2) \geq 0, \end{aligned} \tag{13}$$

where $\mathbf{s}^2 = \boldsymbol{\mu}_\mathbf{x}^1 - \mathbf{x}_{MPP}^1$.

The reliabilities of those violated probabilistic constraints will improve remarkably using this MPP shifting strategy. After the optimization in Cycle 2, the reliability assessment of Cycle 2 is conducted to find the updated MPPs and to check the design feasibility. If some probabilistic constraints are still not satisfied, we repeat the procedure cycle by cycle until the objective converges and the reliability requirement is achieved when all the shifting distances become zero.

As for the general case where deterministic design variables **d** and random design variables **X** as well as the random parameters P exist, deterministic design variables d can be considered as special random variables with zero variances and the sifting distance corresponding to **d** is zero. Since we have no means to control the random parameters **P** in the design, we could not use the same shifting treatment. However, considering model (9), we see that to maintain the reliability requirement, the deterministic constraint function should satisfy $g(\mathbf{d}, \mathbf{x}_{MPP}, \mathbf{p}_{MPP}) \geq 0$. Therefore, for random parameters **P** we simply use the MPP $\mathbf{p}_{MPP}$ obtained in the previous cycle, such that

$$g(\mathbf{d},\ \boldsymbol{\mu}_\mathbf{x} - \mathbf{s}, \mathbf{p}_{MPP}) \geq 0 \tag{14}$$

Based on the same strategy, we derive the general optimization model in Cycle k +1 as

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \mathbf{p}_\mathbf{p}) \\ &DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \\ &\text{Subject to: } g_i(\mathbf{d},\ \mathbf{u}_\mathbf{x} - \mathbf{s}_i^{k+1}, \mathbf{p}_{iMPP}^k) \geq 0, \\ &\text{i=1~m,} \end{aligned} \tag{15}$$

where $\mathbf{s}_i^{k+1} = \boldsymbol{\mu}_\mathbf{x}^k - \mathbf{x}_{iMPP}^k$.

It is noted that since each probabilistic constraint has its own MPP, each probabilistic constraint has its own shifting vector si.

To further improve the efficiency, we also take the following measures: 1) The starting point for MPP search in reliability assessment of the current cycle is taken as the MPP obtained in the last cycle. Since the MPPs of probabilistic constraints in two consecutive cycles are very close, using the MPP of last cycle gives a good initial guess of the MPP in the next cycle, and hence reduces the computational effort for MPP search. 2) Similarly, the starting point of the optimization of one cycle is taken as the optimum point of the previous cycle. 3) After one cycle of optimization, if the design variables concluded in one probabilistic constraint do not change or have very small changes compared with those in the last cycle, the MPP in the current cycle will be the same as or very close to that in the last cycle. Therefore, it is unnecessary to search the MPP again for this probabilistic constraint in the following reliability assessment.

The stopping criteria of the SORA method are as follows: 1) The objective approaches stable: the difference of the objective function between two consecutive cycles are small enough. 2) All the reliability requirements are satisfied.

From the procedure of the SORA method we see that the reliability analysis loop (locating the MPPs) is completely decoupled from the optimization loop and that in the optimization part, equivalent deterministic forms of constraints are used. There is no need to modify the forms of constraint functions. As a result, it is easy to code and to integrate the reliability analysis with any optimization software. We also see that the design is progressively improved (the desired reliability is progressively achieved) in the probabilistic design process. This helps a designer track the design process more efficiently. Since the SORA method requires much less optimization iterations and reliability assessments to converge, the overall efficiency is high.

4. APPLICATIONS

Two engineering design problems are used to demonstrate the effectiveness of the SORA method. These two examples include the reliability-based design for vehicle crashworthiness of side impact and the integrated reliability and robust design for the speed reducer of a small aircraft engine.

4.1 Reliability-Based Design for Vehicle Crashworthiness of Side Impact

The computational analysis of crashworthiness for vehicle impact has become a powerful and efficient tool to reduce the cost and development time for a new product that meets corporate and government crash safety requirements. Since the effects of uncertainties associated with the structure sizes, material properties, and operation conditions in the vehicle impact are considerably of importance, reliability based design optimization for vehicle crashworthiness has been gained increasingly attention and has been conducted in automotive industries (Yang, et al., 1994 and 2001). Typically, in a reliability-based design, the design feasibility is formulated as the reliability constraints while the design objective is related to the nominal value of the objective function. SORA is applied to the reliability-based design for vehicle crashworthiness of side impact based on global response surface models generated by Ford Motor Company.

There are 9 random variables X1 – X9, representing sizes of the structure, material properties (X8 and X9), and 2 random parameters P1 (Barrier height) and P2 (Barrier hitting position).

The reliability-based design model is given in Figure 8.

Find $\mu_i, \quad i = 1, 2, \cdots, 9$

Minimize $\quad \mu_w$ (the mean of the weight)

Subject to $\quad \text{Prob}\{F_{Abdomen\_load} \le 1.0\,\text{(KN)}\} \ge \text{R}_1$

$$\text{Prob}\{VC_1 \le 0.32\,\text{(m/s)}\} \ge \text{R}_2$$
$$\text{Prob}\{VC_2 \le 0.32\,\text{(m/s)}\} \ge \text{R}_3$$
$$\text{Prob}\{VC_3 \le 0.32\,\text{(m/s)}\} \ge \text{R}_4$$
$$\text{Prob}\{D_{low} \le 32\,\text{(mm)}\} \ge \text{R}_5$$
$$\text{Prob}\{D_{middle} \le 32\,\text{(mm)}\} \ge \text{R}_6$$
$$\text{Prob}\{D_{up} \le 32\,\text{(mm)}\} \ge \text{R}_7$$
$$\text{Prob}\{F_{Public} \le 4.01\,\text{(KN)}\} \ge \text{R}_8$$
$$\text{Prob}\{V_{bp} \le 9.9\,\text{(m/s)}\} \ge \text{R}_9$$
$$\text{Prob}\{V_d \le 15.69\,\text{(m/s)}\} \ge \text{R}_{10}$$

Side Constraints:

$$\mu_{li} \le \mu_i \le \mu_{ui},\ i = 1 \sim 7$$
$$\mu_8, \mu_9 = 0.192 \text{ or } 0.345 \text{ (Material properties)}$$

where μ_i (i = 1 ~ 9) are the means of X_i, μ_w is the nominal value of structure weight, and R_i (i=1~10) are desired reliabilities.

Figure 8. Reliability-Based Design Model for Vehicle Crashworthiness of Side Impact

In this design model, w is the weight of the structure, Fs are abdomen load and pubic symphysis force, VCs are viscous criteria, and Ds are rib deflections (upper, middle, and lower).

To verify the proposed method, in addition to the SORA method, the existing DLM_Prob and the DLM_Per strategies are also used to solve the problem. We consider two cases. In Case 1, all the desired reliabilities are set to R=0.9. This is the case used by Ford Motor Company. In Case 2, we use higher reliability, R=0.99865 which is equivalent to the safety index β=3. For all the three methods, the optimization algorithm is the sequential quadratic programming (SQP) and the reliability assessment is based on FORM with the inverse MPP search algorithm developed in Du (2002).

1) Case 1 – Desired Reliability = 0.9

The SORA method uses three cycles of sequential optimizations and reliability assessment to obtain the solution. The optimization history is given in Table 1. The method starts from a conventional deterministic optimization. The result under optimization in cycle 1 in Table 1 is the optimum solution for the deterministic optimization. It is noted that the objective (weight) reduces significantly from 29.172 kg at the baseline (starting point) to 23.5054 kg. After the deterministic optimization, the reliability analysis is performed to locate the MPP for each constraint and it is noted that the reliabilities are low for some constraints such as the deflection of low rib $\text{Prob}\{D_{low} \le 32\,\text{(mm)}\}$ and pubic force $\text{Prob}\{F_{Public} \le 4.01\,\text{(KN)}\}$. Based on the result of the deterministic optimization and the information of the MPPs, the constraints boundaries are shifted as formulated in Eqn. (14) and the feasible region is rearranged (reduced towards feasible directions) for the optimization in Cycle two. After Cycle 2, all the reliability requirements are satisfied. Therefore, the result of Cycle 3 is identical to that of Cycle 2. Cycle 3 is a repeated cycle for convergence purpose. From the result, we see that the desired reliability is progressively achieved and design is quickly improved.

The convergence history of the objective (weight) is depicted in Fig. 9 where cycles distinguish from each other clearly – in each cycle, one reliability assessment follows one optimization. It is noted that most of computations are for reliability analyses. The total number of function evaluations is 491 including 74 for optimizations and 341 for reliability analyses. The average number of function evaluations for reliability analysis during each cycle is 114.

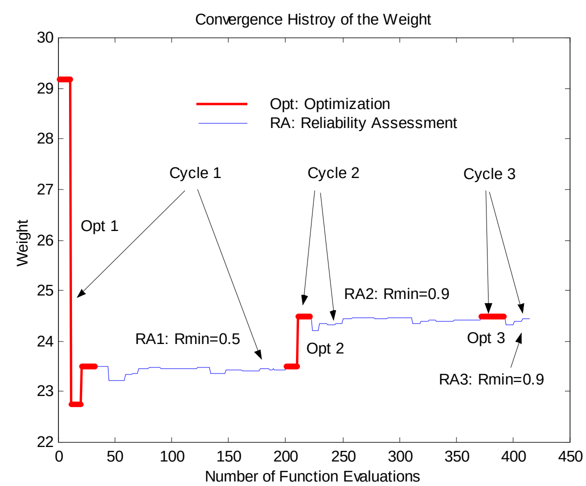

Figure 9. Convergence History of the Object

Our confirmative test shows that SORA has the same accuracy as the double-loop methods (the DLM_Prob and the DLM_Per). However, the DLM_Prob and the DLM_Per require much more function evaluations as shown in Table 2. The numbers of function evaluations required by the DLM_Per and the DLM_Prob are 3324 and 26984, respectively. It is noted that the SORA method is the most efficient and the DLM_per is more efficient than the DLM_Prob.

Table 2. Number of Function Evaluations

Method	NFE for Reliability Assessment	NFE for Optimization	Total NFE
SORA	341	74	415
DLM_Per	–	–	3324
DLM_Prob	–	–	26984

NFE – Number of Function Evaluations

2) Case 2 – Desired Reliability = 0.99865 (β=3)

All the three methods (the SORA method, the DLM_Prob and the DLM_Per) generate the same results as follows:

Table 1. Result of SORA Method for Vehicle Side Impact for Case 1

Cycle 1					
Design Variables		Objective	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50	23.5054	Abdomen_load	0.5727	1.0
μ2	1.2257		Drib_low	32.0000	0.50
μ3	0.50		Drib_m	27.6641	0.9960
μ4	1.1871		Drib_u	29.3721	0.9993
μ5	0.8750		VC1	0.2299	1.0
μ6	0.9139		VC2	0.2029	1.0
μ7	0.40		VC3	0.2925	1.0
μ8	0.3450		Pubic_F	4.0100	0.50
μ9	0.1920		Vbp	9.3423	1.0
			Vd	15.6781	0.5343
Cycle 2					
Design Variables		Objective	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50	24.4897	Abdomen_load	0.4839	1.0
μ2	1.3091		Drib_low	31.1742	0.9001
μ3	0.50		Drib_m	27.1367	0.9985
μ4	1.2938		Drib_u	29.5611	0.9983
μ5	0.8750		VC1	0.2330	1.0
μ6	1.20		VC2	0.2116	1.0
μ7	0.40		VC3	0.2896	1.0
μ8	0.3450		Pubic_F	3.9487	0.90
μ9	0.1920		Vbp	9.2581	0.9996
			Vd	15.4671	0.9749
Cycle 3					
Design Variables		Objective 24.4913	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50		Abdomen_load	0.4838	1.0
μ2	1.3091		Drib_low	31.1742	0.9001
μ3	0.50		Drib_m	27.1367	0.9985
μ4	1.2942		Drib_u	29.5611	0.9983
μ5	0.8750		VC1	0.2330	1.0
μ6	1.20		VC2	0.2116	1.0
μ7	0.40		VC3	0.2896	1.0
μ8	0.3450		Pubic_F	3.9485	0.9004
μ9	0.1920		Vbp	9.2581	0.9996
			Vd	15.4671	0.9749

Note: The reliability =1.0 means that the reliability approaches closely but may not exactly equals to 1.0.

μ_w=28.4397 kg, $R_1=R_3=R_4=R_5=R_6=R_7\approx1.0$, $R_2=R_8=R_{10}=0.99865$. In this case, three constraints (Drib_low, Pubic_F and, vd) are active with the exact reliability of 0.99865. With the SORA method, three sequential cycles of optimization and reliability assessments are used. Since the desired reliability is higher than that in Case 1, the reliability analysis needs more computations. The number of function evaluations for reliability is 446, and the average number for each cycle is 149 which is larger than the one in case 1. The number of function evaluations for optimization is 84 and the total number of function evaluations is 530. The numbers of function evaluations required by the DLM_Per and the DLM_Prob are 3272 and 456195, respectively. Therefore, the SORA method is still the most efficient and the DLM_per is more efficient than the DLM_Prob.

4.2 Integrated Reliability and Robust Design for the Speed Reducer

The speed reducer problem presents the design of a simple gearbox of a small aircraft engine, which allows the engine to rotate at its most efficient speed. This has been used as a testing problem for nonlinear optimization method in the literature. The original design was modeled by Golinski (1970 and 1973) as a single-level optimization, and since then many others have used it to test a variety of methods, for example, as an artificial multidisciplinary optimization problem (Li, 1989; Datseris 1982; Azarm and Li, 1989, Renaud, 1993 and Boden and Grauer, 1995).

Since in the design of the speed reducer there are many random variables, such as the sizes of the components (gears, shafts, etc.), material properties, and operation environment (rotation speed, engine power etc.), it is also a good example for optimization under uncertainty. We modify this problem as a probabilistic design problem by assigning randomness to appropriate variables and parameters.

The deterministic design model of the speed reducer is given in Li (1989). In the probabilistic design, there are two deterministic design variables: $d_1 = m =$ teeth module, and $d_2 = z =$ number of pinion teeth, and five random design variables: $X_1 = b =$ face width, $X_2 = l_1 =$ shaft-length 1 (between bearings), $X_3 = l_2 =$ shaft-length 2 (between bearings), $X_4 = d_1 =$ shaft diameter 1, $X_5 = d_2 =$ shaft diameter 2. There are 15 random parameters $P_1 \sim P_{15}$, including the material properties, the rotation speed, and the engine power, and 11 constraints among which ten (g1~g10) are probabilistic constraints which are related to the bending condition, the compressive stress limitation, the transverse deflection of shafts and the substitute stress conditions, as well as one deterministic constraint g11. The design objective is to minimize the weight of the speed reducer.

The integrated reliability and robust design model is provided as follows:

Find $d_i, \quad i = 1, 2$ and $\mu_j, \quad j = 1, 2, \cdots, 9$

Minimize $w_1 \dfrac{\mu_w}{\mu_{w2}^*} + w_2 \dfrac{\sigma_w}{\sigma_w^*}$

Subject to $\text{Prob}\{g_k \le 0\} \ge \text{R}_\text{k} \quad k = 1, \cdots, 10$

$g_{11} \le 0$

Side Constraints:

$l_{di} \le d_i \le u_{di}, i = 1,2$

$l_{\mu j} \le \mu_j \le u_{\mu j}, i = 1,10$

Figure 10. Integrated Reliability and Robust Design Model

w_1 and w_2 are weighting factors. μ_w^* (obtained by $w_1 = 1$ and $w_2 = 0$) and σ_w^* (obtained by $w_1 = 0$ and $w_2 = 1$) are the ideal solutions used to normalize the two aspects in the objective, i.e., optimizing the mean performance and minimizing performance deviations.

The mean μ_w and the standard deviation of the weight σ_w are evaluated by Taylor expansion at the means of the random variables.

Since we consider the robustness in the design objective and the reliability requirements in the design feasibility, we call this design integrated reliability and robust design.

The desired reliability for all the probabilistic constraints is 0.95. All the three methods, the SORA method, the DLM_Per and the DLM_Prob, are used to solve this problem and the results from them are identical.

A comparison of the total number of function evaluations is provided in Table 3. The number of function evaluations of the SORA method is 338, among which 164 used for optimization and 174 used for reliability assessments. Three cycles are used by SORA to solve the problem. The SORA method is the most efficient method for this problem.

Table 3. Number Of Function Evaluations

Method	NFE for Reliability Assessment	NFE for Optimization	Total NFE
SORA	174	164	338
DLM_Per	–	–	3532
DLM_Prob	–	–	20134

5. DISCUSSIONS AND CONCLUSION

The purpose of developing the SORA method is to improve the efficiency of probabilistic design. Different from the existing double loop methods, the SORA method employs the strategy of sequential single loops for optimization and reliability assessment, which separates the reliability assessment from the optimization loop. The measures taken by SORA include the use of the percentile formulation for the probabilistic constraints instead of the reliability formulation to avoid evaluating the actual reliabilities; the use of sequential cycles of optimization and reliability assessments to reduce the total number of reliability analyses; and the use of an efficient and robust inverse MPP search algorithm to perform the reliability assessments.

The combination of these measures formulates a serial of “equivalent” deterministic optimization problems in such a way that the optimum solution can be identified progressively and quickly. The probabilistic constraints are formulated as the deterministic constraint functions (for R percentile evaluations), which are evaluated at their MPPs. As a result, there is no need to perform reliability assessment within each optimization. If the design objective is deterministic, such as those in reliability-based design, there is no need to perform any probabilistic analysis in the optimization process. Therefore, the SORA method is extremely efficient for reliability-based optimization. As demonstrated in Example 1, the SORA method has much higher efficiency than the double loop methods. When the objective is formulated probabilistically, for example, the design objective is related to both the mean and standard deviation of the objective function for a robust design, or the design objective is the expected utility in the utility optimization, the SORA method is still applicable. However, its efficiency depends on how to evaluate the probabilistic characteristics of the objective function. If computationally expensive methods, such as the sampling method, are employed, the efficiency will decrease. If deterministically equivalent methods are used to evaluate the probabilistic objective, the efficiency of the SORA method will still be acceptable. One example of this treatment is demonstrated by the integrated reliability and robust design for the speed reducer presented in Section 4, where we employed the Taylor expansion to evaluate the mean and the standard deviation of the objective function.

There is a potential to further improve the efficiency of the SORA method. Some of the probabilistic constraints are never active during the whole design process and their reliabilities are always above the desired levels. Therefore, it is not necessary to evaluate the percentiles of those constraints in the reliability assessment in each cycle. By investigating the method to identify the never-active probabilistic constraints can avoid unnecessary reliability assessments and hence can improve the efficiency considerably.

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SEQUENTIAL OPTIMIZATION AND RELIABILITY ASSESSMENT METHOD FOR EFFICIENT PROBABILISTIC DESIGN

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ABSTRACT

Probabilistic optimization design offers tools for making reliable decisions with the consideration of uncertainty associated with design variables/parameters and simulation models. In a probabilistic design, such as reliability-based design and robust design, the design feasibility is formulated probabilistically such that the probability of the constraint satisfaction (reliability) exceeds the desired limit. The reliability assessment for probabilistic constraints often involves an iterative procedure; therefore, two loops are involved in a probabilistic optimization. Due to the double-loop procedure, the computational demand is extremely high.

To improve the efficiency of a probabilistic design, a novel method – sequential optimization and reliability assessment (SORA) is developed in this paper. The SORA method employs a single-loop strategy where a serial of cycles of optimization and reliability assessment is employed. In each cycle optimization and reliability assessment are decoupled from each other; no reliability assessment is required within optimization and the reliability assessment is only conducted after the optimization. The key concept of the proposed method is to shift the boundaries of violated deterministic constraints (with low reliability) to the feasible direction based on the reliability information obtained in the previous cycle. Hence the design is quickly improved from cycle to cycle and the computational efficiency is improved significantly. Two engineering applications, the reliability-based design for vehicle crashworthiness of side impact and the integrated reliability and robust design of a speed reducer, are presented to demonstrate the effectiveness of the SORA method.

1. INTRODUCTION

Traditional optimization designs are pushed to the limits of system failure boundaries, leaving very little or no room for accommodating uncertainties in engineering design. Consequently, deterministic optimization designs obtained without any consideration of uncertainties may be sensitive to the variation of system (leading to quality loss), risky (high likelihood of undesired events or low constraint satisfaction), or conservative and therefore uneconomic if deterministic safety factors are larger than required. It is therefore important to incorporate uncertainty in engineering design optimization and develop computational techniques that enable engineers to make efficient and reliable decisions.

Probabilistic design methods have been developed and have been applied in engineering design. The typical probabilistic design methods include reliability-based design (Wu and Wang, 1996; Carter, 1997; Grandhi and Wang, 1998) and robust design (Chen, et al, 1996; Du and Chen, 2000a). Reliability-based design emphasizes high reliability of a design by ensuring the probabilistic constraint satisfaction at desired levels, while robust design focuses on making the design inert to the variations of system input through optimizing mean performance of the system and minimizing its variance simultaneously. One important task of a probabilistic design is uncertainty analysis, through which we understand how much the impact of the uncertainty associated with the system input is on the system output by identifying the probabilistic characteristics of system output. We then perform synthesis (optimization) under uncertainty to achieve our design objective by managing and mitigating the effects of uncertainty on system output (system performance) (Du and Chen, 2000b).

In spite of the benefits of probabilistic design, one of the most challenging issues for implementing probabilistic design is associated with the intensive computational demand of uncertainty analysis. To capture the probabilistic characteristics of system performance at a design point, we need to perform a number of deterministic analyses in the vicinity of the nominal point, either using simulation approach (for instance, Monte Carlo simulation) or other probabilistic analysis methods (such as reliability analysis). Many researches have been concentrating on developing practical means to make probabilistic design computationally feasible for complex engineering problems.

Our focus in this study is to develop an efficient probabilistic design approach to facilitate design optimizations that involve probabilistic constraints. Reliability-based design is such type of probabilistic optimization problems (Reddy, et al., 1993; Wang, et al., 1995; Chen and Hasselman, 1997; Tu; et al., 1999) in which design feasibility is formulated as reliability constraints (or the probability of constraint satisfaction). The conventional approach for solving a probabilistic optimization problem is to employ a double-loop strategy in which the analysis and the synthesis are nested in such a way that the synthesis loop (outer loop) performs the uncertainty analysis (inner loop for reliability assessment) iteratively for meeting the probabilistic objective and constraints. As the double-loop strategy may be computationally infeasible, various techniques have been developed to improve its efficiency. These techniques can be classified into two categories: one is through improving the efficiency of uncertainty analysis methods, for example, the methods of Fast Probability Integration (Wu, 1994) and Two-Point Adaptive Nonlinear Approximations (Grandhi and Wang, 1998); the other is through modifying the formulation of probabilistic constraints, for example, the performance measure approach (Tu and Choi, 1999). A comprehensive review of various feasibility modeling approaches for design under uncertainty is provided in Du and Chen (2000b).

Even though the improved uncertainty analysis techniques and modifications of problem formulation have lead to improved efficiency of probabilistic optimization, the improvement is quite limited due to the nature of the double loop strategy. Recent years have seen preliminary studies on a new type of method - single loop method (Chen and Hasselman, 1997; Wu, et al., 2001). In Wu's work, a method of "approximately equivalent deterministic constraints" is developed, which creates a link between a probabilistic design and a safety-factor based design. In Chen's work, the reliability constraints are formulated as deterministic constraints that approximate the condition of the Most Probable Point (MPP) (Hasofer and Lind, 1974), a concept used for reliability assessment. Although the single loop strategy appears promising as no nested synthesis and uncertainty analysis loops are involved because the probabilistic constraints are approximated by the equivalent deterministic constraints, these methods are relatively new and will require further investigations and verifications that can illustrate their improvement over the double-loop strategy by testing various applications.

In this paper, we present a new probabilistic design method, Sequential Optimization and Reliability Assessment (SORA) that we believe can significantly improve the efficiency of probabilistic optimization. Our method employs a single loop strategy which decouples optimization synthesis and uncertainty analysis. As an integral part of the proposed strategy, we employ the formulation of performance measure for the reliability constraints along with an efficient inverse MPP search algorithm. In this paper, we will first review a few commonly used strategies of probabilistic design in Section 2. The review will lay the foundation for our proposed method, SORA, introduced in Section 3. In Section 4 two engineering examples are used to illustrate the effectiveness of the proposed method. Section 5 is the closure, which highlights the effectiveness of the proposed method and provides discussions on its applicability under different circumstances.

2. PROBABILISTIC OPTIMIZATION STRATEGIES

In this section, we present two commonly used probabilistic design strategies, which lay the foundation for our proposed method. These two strategies are also used for the purpose of comparison when verifying our proposed method.

2.1 Double-Loop Strategy with Probabilistic Formulation

A typical model of a probabilistic design is given by:

Minimize: $f(\mathbf{d}, \mathbf{X}, \mathbf{P})$

Design Variable $DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\}$ (1)

Subject to: $\text{Prob}\{g_i(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0\} \geq R_i$, i=1~m,

where f is an objective function, d is the vector of deterministic design variables, X is the vector of random design variables, P is the vector of random design parameters, g_i(**d**, **X**, **P**) (i=1~m) are constraint functions, R_i are desired probabilities of constraint satisfaction, and m is the number of constraints. The design variables are **d** and the means ($\boldsymbol{\mu}_x$) of the random design variables **X**. Note that the following rules of symbols are used to differentiate the representation of random variables, deterministic variables, and vectors. A capital letter is used for a random variable, a lower case letter for a deterministic variable or a realization of a random variable, and a bold letter is used for a vector. For example, X stands for a random variable and x for a deterministic variable or a realization of random variable X; **X** denotes a vector of random variables while **x** denotes a vector of deterministic variables.

In the above probabilistic design model, the design feasibility is formulated as the probability (Prob) of constraint satisfaction $g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0$ bigger than or equal to a desired probability R. As shown in Fig. 1, the probability of $g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0$ is the area underneath the curve of probability density function (PDF) of g for g≥0, and this area should be greater than or equal to R.

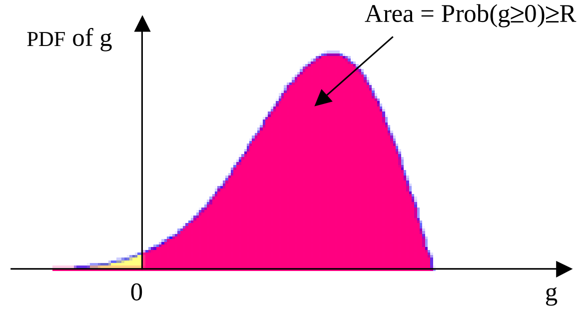

Figure 1. PDF of a Constraint Function g

The probability of constraint satisfaction is also called reliability. Analytically, the reliability is given by the integral

$$\text{Prob}\{g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0\} = \int \cdots \int_{g(\mathbf{d}, \mathbf{X}, \mathbf{P}) \geq 0} f_{\mathbf{X}, \mathbf{P}}(\mathbf{x}, \mathbf{p}) d\mathbf{x} d\mathbf{p} , \quad (2)$$

where $f_{\mathbf{X},\mathbf{P}}(\mathbf{x},\mathbf{p})$ is the joint probability density function of **X** and **P**, and the probability is evaluated by the multidimensional integration over the region $g(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0$. It is generally difficult or even impossible to perform the multidimensional integration in Eqn. (2). One alternative method to evaluate the integration is Monte Carlo simulation. However, when the reliability is very high (approaching 1.0), the computational effort of Monte Carlo Simulation is prohibitively expensive (Du and Chen, 2000b). Hasofer and Lind (1974) proposed the concept of the Most Probable Point (MPP) in the structural reliability field to approximate the integration.

With the MPP approach, the random variables $(\mathbf{X},\mathbf{P})$ are transformed into an independent and standardized normal space $(\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P})$. The MPP is formally defined in the standardized normal space as the minimum distance point on the constraint boundary $g(\mathbf{d},\mathbf{X},\mathbf{P})=g(\mathbf{d},\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P})=0$ to the origin. The minimum distance β is called reliability index. When the First Order Reliability Method (FORM) (Hasofer and Lind, 1974) is used, the reliability is given by

$$\text{Prob}\{g(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0\}=\Phi(\beta), \tag{3}$$

where Φ is the standard normal distribution function. Finding the MPP and the reliability index is a minimization problem, which usually involves an iterative searching process. Therefore, the reliability assessment itself is an optimization problem. For details about the MPP based method, refer to Du and Chen (2001a).

When the probability formulation in design model (1) is directly used to solve the problem, the method is called "double-loop method with probability formulation" (DLM_Prob) (Reddy, et al., 1993; Wang, et al., 1995; Tu; et al., 1999). The efficiency of this type of method is usually low since it employs nested optimization loops to first evaluate the reliability of each probabilistic constraint and then to optimize the design objective subject to the reliability requirements.

2.2 Double-Loop Strategy with Percentile Formulation

An equivalent model to (1) is given by (Tu, et al., 1999; Choi and Youn, 2001; Wu, et al, 2001)

Minimize: $f(\mathbf{d},\mathbf{X},\mathbf{P})$

$$DV=\{\mathbf{d},\boldsymbol{\mu}_\mathbf{x}\} \tag{4}$$

Subject to: $g_i^R(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0$, i=1~m,

where g^R is the R- percentile of $g(\mathbf{d},\mathbf{X},\mathbf{P})$, namely,

$$\text{Prob}\{g(\mathbf{d},\mathbf{X},\mathbf{P})\geq g^R\}=R \tag{5}$$

Eqn. (5) indicates that the probability of $g_i(\mathbf{d},\mathbf{X},\mathbf{P})$ greater than or equal to the R-percentile g^R is exactly equal to the desired reliability *R*. The concept is demonstrated in Fig. 2. If the shaded area is equal to the desired reliability *R*, then the left ending point g^R on the g axis is called the R-percentile of function g. From Fig. 2 we see that, if $g^R\geq 0$, it indicates that $\text{Prob}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0\}\geq R$. Therefore, the original constraints that require the reliability assessment are now converted to constraints that evaluate the R-percentile.

The percentile g^R can be evaluated by the inverse MPP method based on FORM, given the desired reliability *R*, the reliability index β is first calculated by

$$\beta=\Phi^{-1}(R) \tag{6}$$

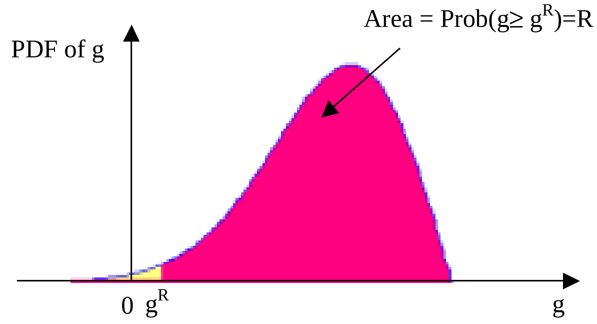

Figure 2. R - Percentile of A Constraint Function

The inverse MPP problem is formulated as shown in the following minimization model,

$$\begin{cases}\text{minimize } g(\mathbf{U})\\ \text{subject to } (\mathbf{U}^T\mathbf{U})^{1/2}=\beta,\end{cases} \tag{7}$$

where $\mathbf{U}=(\mathbf{U}_\mathbf{X},\mathbf{U}_\mathbf{P})$.

Using an inverse MPP search algorithm, the optimum solution MPP $\mathbf{u}_{MPP}$ can be identified and the R percentile is evaluated by

$$g^R=g(\mathbf{u}_{MPP})=g(\mathbf{x}_{MPP},\mathbf{p}_{MPP}). \tag{8}$$

To some extent, the evaluation of Eqn. (8) can be viewed as deterministic by substituting the MPP values ($\mathbf{x}_{MPP}$ and $\mathbf{p}_{MPP}$ in the original random space) directly into the *g* function. Since applying the inverse MPP method also involves iterative procedures, we call the method for solving model (4) "the double-loop method with percentile formulation" (DLM_Per). It is also called performance measure approach (PMA) in (Tu, et al., 1999; Choi and Youn, 2001).

To distinguish the type of function evaluations for the probabilistic constraints (Eqns. (3) or (8)) from those for the original constrain functions $g(\mathbf{d},\mathbf{X},\mathbf{P})$, we call the function evaluations for the reliabilities $\text{Prob}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0\}$ or the R-percentile $g^R=g(\mathbf{u}_{MPP})=g(\mathbf{x}_{MPP},\mathbf{p}_{MPP})$ "probabilistic function evaluations" and those for the original function $g(\mathbf{d},\mathbf{X},\mathbf{P})$ "the performance function evaluations" or simply "the function evaluations".

For both DLM_Prob and DLM_Per, to fulfill the optimization, the outer loop optimizer calls the objective function and probabilistic constraints repeatedly as illustrated in Fig. 3. Therefore, the total number of function evaluations will be huge. For instance, assume that the outer optimization loop needs 100 probabilistic function evaluations and that there are 10 probabilistic constraints, if each probability evaluation needs 50 function evaluations on average, the total number of function evaluations would be 100×10×50=50,000!

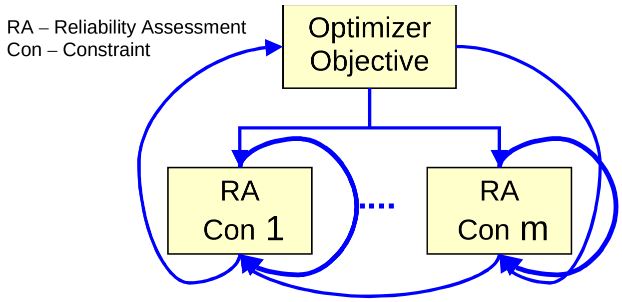

Figure 3. Double Loop Methods

3. Sequential Optimization and Reliability Assessment (SORA) Method

To improve the efficiency of probabilistic optimization, we adopt in this work the strategy of "serial single loops" (Chen and Hasselman, 1997; Wu, et al., 2001) to develop an efficient, sequential optimization and reliability assessment (SORA) method. Our proposed method is different from the existing single loop methods in the way that we establish the equivalent deterministic constraint of the probabilistic constraint. We also employ an efficient inverse MPP search algorithm as an integral part of the proposed procedure.

3.1 The Measures Taken in Developing the SORA Method

In developing the SORA method, several measures have been taken, including evaluating the reliability only at the desired level (R-percentile), using an efficient and robust inverse MPP search algorithm, and employing sequential cycles of optimization and reliability assessment.

(1) Evaluating the reliability only at the desired level (R-percentile)

It is noted that in probabilistic optimization, the closer the reliability $\mathrm{P}\{g_i(\mathbf{d},\mathbf{X},\mathbf{P})\geq 0\}$ is to 1.0, the more computational effort is required. For using the MPP based methods, the higher reliability means larger search region in the standardized normal space to locate the MPP and it is very likely that more function evaluations are required. In probabilistic optimization with multiple constraints, some constraints may never be active and their reliabilities are extremely high (approaching 1). Although these constraints are the least critical, the evaluations of these reliabilities will unfortunately dominate the computational effort in the probabilistic design process if the DLM_Prob strategy (Section 2.1) is employed. The solution to this problem is to perform the reliability assessment only up to the necessary level, represented by the desired reliability *R*.

To this end, we use the percentile formulation for probabilistic constraints with the SORA method. Based on Eqn. (8), the design model (5) of DLM_Per is rewritten as

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d},\boldsymbol{\mu}_{\mathbf{x}}) \\ &DV=\{\mathbf{d},\boldsymbol{\mu}_{\mathbf{x}}\} \qquad (9) \\ &\text{Subject to: } g_i(\mathbf{d},\mathbf{x}_{MPPi},\mathbf{p}_{MPPi})\geq 0,\ \text{i=1~m} \end{aligned}$$

This model establishes the equivalence between a probabilistic optimization and a deterministic optimization since the original constraint functions $g_i(\mathbf{d},\mathbf{x}_{MPPi},\mathbf{p}_{MPPi})$ are used to evaluate design feasibility using the MPPs corresponding to the desired reliabilities Ri. Fig. 4 is used to further explain how a probabilistic constraint is converted to an equivalent deterministic constraint. With two random design variables X_1 and X_2 as an example, we see that the feasible region of a probabilistic design is a reduced region in comparison with a deterministic feasible design. Evaluation of a probabilistic constraint at design solution (μ_{x1}, μ_{x2}) is equivalent to evaluating the deterministic constraint at the MPP point, i.e., $g(\mathbf{d},\mathbf{x}_{MPP},\mathbf{p}_{MPP})$. As shown in Fig. 4, the MPP corresponding to the design point on the probabilistic constraint boundary is exactly on the deterministic constraint boundary. When $g(\mathbf{d},\mathbf{x}_{MPP},\mathbf{p}_{MPP})=0$, it indicates that the shaded area of the probability density function curve of $g(\mathbf{d},\mathbf{X},\mathbf{P})$ is equal to 1-*R* where *R* is the desired reliability. Therefore, to maintain the design feasibility, the MPP of each probabilistic constraint should be within the deterministic feasible region.

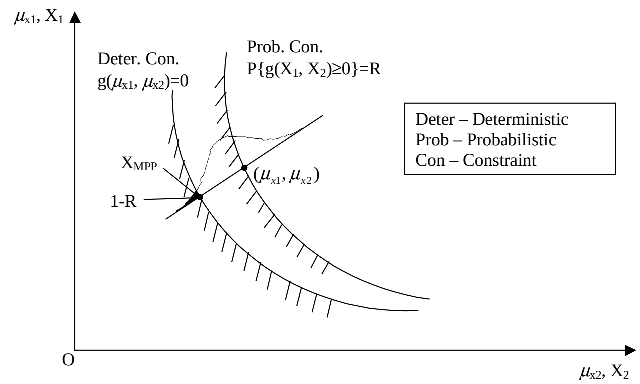

Figure 4. Probabilistic Constraint

(2) Using an efficient and robust inverse MPP search algorithm

In SORA, we employ an efficient MPP based percentile evaluation method (inverse MPP search algorithm) of which principle is introduced in (Du and Chen, 2001a) with more details documented in (Du, 2002). This new MPP search algorithm combines several techniques, such as using the steepest decent direction as the search direction, performing an arc search if no progress is made along the steepest decent direction, and adopting the adaptive step size for numerical derivative evaluation. This search algorithm is considered robust since it is suitable for any continuous constraint functions (including non-concave and non-convex functions) and continuous distributions of uncertainty.

(3) Employing sequential cycles of optimization and reliability assessment

It is noted that in a probabilistic design, most of the computations are used for reliability assessments. Therefore, to improve the overall efficiency of probabilistic optimization we need to reduce the number of reliability assessments as much as possible. The essence is to move the design solution as quickly as possible to its optimum so as to reduce the needs for locating MPPs. To achieve this, SORA employs a serial of cycles of optimization and reliability assessment. Each cycle includes two parts, one part is the (deterministic) optimization and another part is the reliability assessment (see Fig.5). The reliability assessment refers to the evaluation of R-percentile corresponding to a given reliability R. In each cycle, at first we solve an equivalent deterministic optimization problem, which is formulated by the information of the MPPs obtained in the last cycle. Once the design solution is updated, we then perform reliability assessment to identify the new MPPs and to check if all the reliability requirements are satisfied. If not, we use the current MPPs to formulate the constraint for the deterministic optimization in the next cycle in which the constraint boundary will be shifted to the feasible region by changing the locations of design variables. Using this strategy, the reliability of constraints improves progressively and the solution to a probabilistic design can be found within a few cycles, and the need for searching MPPs can be reduced significantly. Detailed flowchart and procedure are provided in Section 3.2.

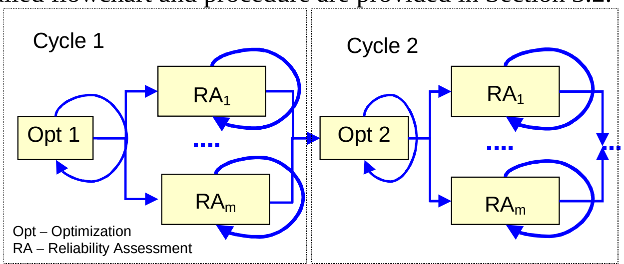

Figure 5. The SORA Method

3.2 SORA Flowchart and Procedure

The flowchart of the SORA method is provided in Fig. 6. For the first cycle, there is no information about the MPPs and they are set as the means of the random design variables and the random parameters. The following optimization in the first cycle is merely a conventional (deterministic) optimization,

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \mathbf{p}_\mathbf{p}) \\ &DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \qquad (10) \\ &\text{Subject to: } g_i(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p}) \geq 0 \text{ , i=1~m} \end{aligned}$$

To demonstrate the strategy of separating (deterministic) optimization and reliability assessment while ensuring both segments work together to bring the design solution quickly to a feasible and optimal solution, we use the same illustrative plot (no deterministic design variables d and random parameters P) as shown in Fig. 4 for demonstration. We start our explanation for the first cycle and then extend the same principle to the kth cycle. In the first cycle, after solving model (10) (deterministic optimization), some of the constraints may become active. For an active constraint g, the optimal point $\boldsymbol{\mu}_x^1 = (\mu_{x1}^1, \mu_{x2}^1)$ is on the boundary of the deterministic constraint function $g(\boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p})$. When considering the randomness of X, as seen on the graph (Fig. 7), the actual reliability (probability of constraint being feasible) is around 0.5. Following the deterministic optimization, the reliability assessment is implemented for the deterministic optimum solution $\boldsymbol{\mu}_x^1 = (\mu_{x1}^1, \mu_{x2}^1)$ to locate the MPP that corresponds to the desired R level. As one can expect, the MPP $\mathbf{x}_{MPP}^1$ of constraint $g(\boldsymbol{\mu}_\mathbf{x}, \boldsymbol{\mu}_\mathbf{p})$ will fall outside (to the left of) the deterministic feasible region. From our discussion in Section 3.1, we know that to ensure the feasibility of a probabilistic constraint, the MPP corresponding to the R percentile should fall within the deterministic feasible region. Therefore, when establishing the equivalent deterministic optimization model in Cycle 2, the constraints should be modified to shift the MPP at least onto the deterministic boundary to help insure the feasibility of the probabilistic constraint. If we use s to denote the shifting vector, the new constraint in the deterministic optimization of the next cycle is formulated as

$$g(\boldsymbol{\mu}_\mathbf{x} - \mathbf{s}) \geq 0 \qquad (11)$$

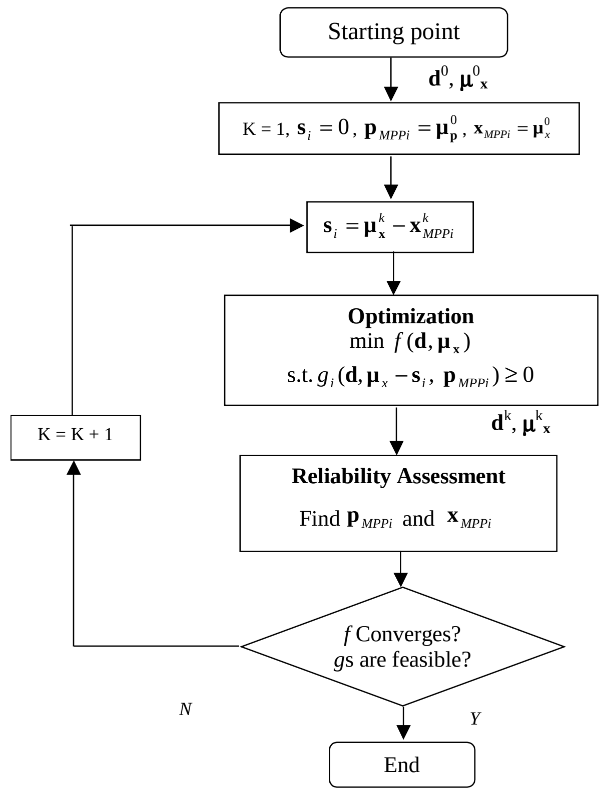

Figure 6. Flowchart of the SORA Method

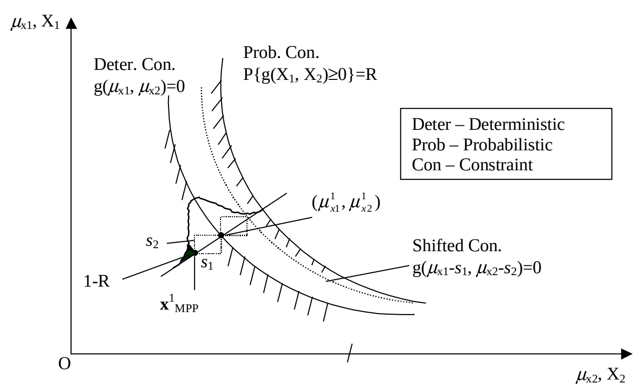

Figure 7. Shifting Constraint Boundary

From Fig. 7, to ensure the MPP onto the deterministic boundary, we derive the shifting vector as

$$\mathbf{s} = (s_1, s_2) = \boldsymbol{\mu}_\mathbf{x}^1 - \mathbf{x}_{MPP} = (\mu_{x1}^1 - x_{1MPP}^1, \mu_{x2}^1 - x_{2MPP}^1). \qquad (12)$$

Correspondingly, Eqn. 11 indicates that the location of the design variables ($\boldsymbol{\mu}_x$) in the deterministic optimization model needs to move further to the boundary of the probabilistic constraint to ensure feasibility under uncertainty. This shifted constraint boundary is shown in Fig. 7 by the dotted curve which is the shifted deterministic constraint curve using the shifting vectors. If there are more than one probabilistic constraints, other constraint boundaries are also shifted towards the feasible region by the distance between the optimal point $\boldsymbol{\mu}_x^1 = (\mu_1^1, \mu_1^2)$ and their own MPPs accordingly. In the optimization of the second cycle, the new constraints form a narrower feasible region in comparison with the one in the first cycle as shown in the following optimization model:

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}) \\ &DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \\ &\text{Subject to: } g(\mathbf{d},\ \mathbf{u}_\mathbf{x} - \mathbf{s}^2) \ge 0, \end{aligned} \tag{13}$$

where $\mathbf{s}^2 = \boldsymbol{\mu}_\mathbf{x}^1 - \mathbf{x}_{MPP}^1$.

The reliabilities of those violated probabilistic constraints will improve remarkably using this MPP shifting strategy. After the optimization in Cycle 2, the reliability assessment of Cycle 2 is conducted to find the updated MPPs and to check the design feasibility. If some probabilistic constraints are still not satisfied, we repeat the procedure cycle by cycle until the objective converges and the reliability requirement is achieved when all the shifting distances become zero.

As for the general case where deterministic design variables **d** and random design variables **X** as well as the random parameters P exist, deterministic design variables d can be considered as special random variables with zero variances and the sifting distance corresponding to **d** is zero. Since we have no means to control the random parameters **P** in the design, we could not use the same shifting treatment. However, considering model (9), we see that to maintain the reliability requirement, the deterministic constraint function should satisfy $g(\mathbf{d}, \mathbf{x}_{MPP}, \mathbf{p}_{MPP}) \ge 0$. Therefore, for random parameters **P** we simply use the MPP $\mathbf{p}_{MPP}$ obtained in the previous cycle, such that

$$g(\mathbf{d},\ \boldsymbol{\mu}_\mathbf{x} - \mathbf{s}, \mathbf{p}_{MPP}) \ge 0 \tag{14}$$

Based on the same strategy, we derive the general optimization model in Cycle k +1 as

$$\begin{aligned} &\text{Minimize: } f(\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}, \mathbf{p}_\mathbf{p}) \\ &DV = \{\mathbf{d}, \boldsymbol{\mu}_\mathbf{x}\} \\ &\text{Subject to: } g_i(\mathbf{d},\ \mathbf{u}_\mathbf{x} - \mathbf{s}_i^{k+1}, \mathbf{p}_{iMPP}^k) \ge 0, \\ &\text{i=1~m,} \end{aligned} \tag{15}$$

where $\mathbf{s}_i^{k+1} = \boldsymbol{\mu}_\mathbf{x}^k - \mathbf{x}_{iMPP}^k$.

It is noted that since each probabilistic constraint has its own MPP, each probabilistic constraint has its own shifting vector si.

To further improve the efficiency, we also take the following measures: 1) The starting point for MPP search in reliability assessment of the current cycle is taken as the MPP obtained in the last cycle. Since the MPPs of probabilistic constraints in two consecutive cycles are very close, using the MPP of last cycle gives a good initial guess of the MPP in the next cycle, and hence reduces the computational effort for MPP search. 2) Similarly, the starting point of the optimization of one cycle is taken as the optimum point of the previous cycle. 3) After one cycle of optimization, if the design variables concluded in one probabilistic constraint do not change or have very small changes compared with those in the last cycle, the MPP in the current cycle will be the same as or very close to that in the last cycle. Therefore, it is unnecessary to search the MPP again for this probabilistic constraint in the following reliability assessment.

The stopping criteria of the SORA method are as follows: 1) The objective approaches stable: the difference of the objective function between two consecutive cycles are small enough. 2) All the reliability requirements are satisfied.

From the procedure of the SORA method we see that the reliability analysis loop (locating the MPPs) is completely decoupled from the optimization loop and that in the optimization part, equivalent deterministic forms of constraints are used. There is no need to modify the forms of constraint functions. As a result, it is easy to code and to integrate the reliability analysis with any optimization software. We also see that the design is progressively improved (the desired reliability is progressively achieved) in the probabilistic design process. This helps a designer track the design process more efficiently. Since the SORA method requires much less optimization iterations and reliability assessments to converge, the overall efficiency is high.

4. APPLICATIONS

Two engineering design problems are used to demonstrate the effectiveness of the SORA method. These two examples include the reliability-based design for vehicle crashworthiness of side impact and the integrated reliability and robust design for the speed reducer of a small aircraft engine.

4.1 Reliability-Based Design for Vehicle Crashworthiness of Side Impact

The computational analysis of crashworthiness for vehicle impact has become a powerful and efficient tool to reduce the cost and development time for a new product that meets corporate and government crash safety requirements. Since the effects of uncertainties associated with the structure sizes, material properties, and operation conditions in the vehicle impact are considerably of importance, reliability based design optimization for vehicle crashworthiness has been gained increasingly attention and has been conducted in automotive industries (Yang, et al., 1994 and 2001). Typically, in a reliability-based design, the design feasibility is formulated as the reliability constraints while the design objective is related to the nominal value of the objective function. SORA is applied to the reliability-based design for vehicle crashworthiness of side impact based on global response surface models generated by Ford Motor Company.

There are 9 random variables X1 – X9, representing sizes of the structure, material properties (X8 and X9), and 2 random parameters P1 (Barrier height) and P2 (Barrier hitting position).

The reliability-based design model is given in Figure 8.

$$\begin{aligned}
&\text{Find } \mu_i, \quad i = 1, 2, \cdots, 9\\
&\text{Minimize} \quad \mu_w \text{ (the mean of the weight)}\\
&\text{Subject to} \quad \text{Prob}\{F_{Abdomen_load} \le 1.0\,(\text{KN})\} \ge R_1\\
&\qquad \text{Prob}\{VC_1 \le 0.32\,(\text{m/s})\} \ge R_2\\
&\qquad \text{Prob}\{VC_2 \le 0.32\,(\text{m/s})\} \ge R_3\\
&\qquad \text{Prob}\{VC_3 \le 0.32\,(\text{m/s})\} \ge R_4\\
&\qquad \text{Prob}\{D_{low} \le 32\,(\text{mm})\} \ge R_5\\
&\qquad \text{Prob}\{D_{middle} \le 32\,(\text{mm})\} \ge R_6\\
&\qquad \text{Prob}\{D_{up} \le 32\,(\text{mm})\} \ge R_7\\
&\qquad \text{Prob}\{F_{Public} \le 4.01\,(\text{KN})\} \ge R_8\\
&\qquad \text{Prob}\{V_{bp} \le 9.9\,(\text{m/s})\} \ge R_9\\
&\qquad \text{Prob}\{V_d \le 15.69\,(\text{m/s})\} \ge R_{10}\\
&\text{Side Constraints:}\\
&\qquad \mu_{li} \le \mu_i \le \mu_{ui},\ i = 1 \sim 7\\
&\qquad \mu_8, \mu_9 = 0.192 \text{ or } 0.345 \text{ (Material properties)}
\end{aligned}$$

where μ_i (i = 1 ~ 9) are the means of X_i, μ_w is the nominal value of structure weight, and R_i (i=1~10) are desired reliabilities.

Figure 8. Reliability-Based Design Model for Vehicle Crashworthiness of Side Impact

In this design model, w is the weight of the structure, Fs are abdomen load and pubic symphysis force, VCs are viscous criteria, and Ds are rib deflections (upper, middle, and lower).

To verify the proposed method, in addition to the SORA method, the existing DLM_Prob and the DLM_Per strategies are also used to solve the problem. We consider two cases. In Case 1, all the desired reliabilities are set to R=0.9. This is the case used by Ford Motor Company. In Case 2, we use higher reliability, R=0.99865 which is equivalent to the safety index β=3. For all the three methods, the optimization algorithm is the sequential quadratic programming (SQP) and the reliability assessment is based on FORM with the inverse MPP search algorithm developed in Du (2002).

1) Case 1 – Desired Reliability = 0.9

The SORA method uses three cycles of sequential optimizations and reliability assessment to obtain the solution. The optimization history is given in Table 1. The method starts from a conventional deterministic optimization. The result under optimization in cycle 1 in Table 1 is the optimum solution for the deterministic optimization. It is noted that the objective (weight) reduces significantly from 29.172 kg at the baseline (starting point) to 23.5054 kg. After the deterministic optimization, the reliability analysis is performed to locate the MPP for each constraint and it is noted that the reliabilities are low for some constraints such as the deflection of low rib $\text{Prob}\{D_{low} \le 32\,(\text{mm})\}$ and pubic force $\text{Prob}\{F_{Public} \le 4.01\,(\text{KN})\}$. Based on the result of the deterministic optimization and the information of the MPPs, the constraints boundaries are shifted as formulated in Eqn. (14) and the feasible region is rearranged (reduced towards feasible directions) for the optimization in Cycle two. After Cycle 2, all the reliability requirements are satisfied. Therefore, the result of Cycle 3 is identical to that of Cycle 2. Cycle 3 is a repeated cycle for convergence purpose. From the result, we see that the desired reliability is progressively achieved and design is quickly improved.

The convergence history of the objective (weight) is depicted in Fig. 9 where cycles distinguish from each other clearly – in each cycle, one reliability assessment follows one optimization. It is noted that most of computations are for reliability analyses. The total number of function evaluations is 491 including 74 for optimizations and 341 for reliability analyses. The average number of function evaluations for reliability analysis during each cycle is 114.

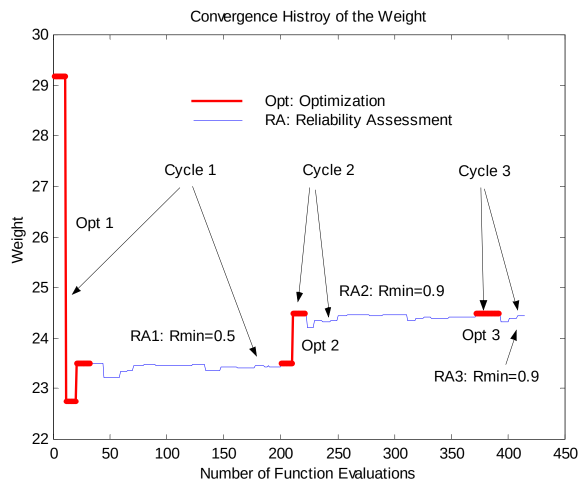

Figure 9. Convergence History of the Object

Our confirmative test shows that SORA has the same accuracy as the double-loop methods (the DLM_Prob and the DLM_Per). However, the DLM_Prob and the DLM_Per require much more function evaluations as shown in Table 2. The numbers of function evaluations required by the DLM_Per and the DLM_Prob are 3324 and 26984, respectively. It is noted that the SORA method is the most efficient and the DLM_per is more efficient than the DLM_Prob.

Table 2. Number of Function Evaluations

Method	NFE for Reliability Assessment	NFE for Optimization	Total NFE
SORA	341	74	415
DLM_Per	–	–	3324
DLM_Prob	–	–	26984

NFE – Number of Function Evaluations

2) Case 2 – Desired Reliability = 0.99865 (β=3)

All the three methods (the SORA method, the DLM_Prob and the DLM_Per) generate the same results as follows:

Table 1. Result of SORA Method for Vehicle Side Impact for Case 1

Cycle 1					
Design Variables		Objective	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50	23.5054	Abdomen_load	0.5727	1.0
μ2	1.2257		Drib_low	32.0000	0.50
μ3	0.50		Drib_m	27.6641	0.9960
μ4	1.1871		Drib_u	29.3721	0.9993
μ5	0.8750		VC1	0.2299	1.0
μ6	0.9139		VC2	0.2029	1.0
μ7	0.40		VC3	0.2925	1.0
μ8	0.3450		Pubic_F	4.0100	0.50
μ9	0.1920		Vbp	9.3423	1.0
			Vd	15.6781	0.5343
Cycle 2					
Design Variables		Objective	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50	24.4897	Abdomen_load	0.4839	1.0
μ2	1.3091		Drib_low	31.1742	0.9001
μ3	0.50		Drib_m	27.1367	0.9985
μ4	1.2938		Drib_u	29.5611	0.9983
μ5	0.8750		VC1	0.2330	1.0
μ6	1.20		VC2	0.2116	1.0
μ7	0.40		VC3	0.2896	1.0
μ8	0.3450		Pubic_F	3.9487	0.90
μ9	0.1920		Vbp	9.2581	0.9996
			Vd	15.4671	0.9749
Cycle 3					
Design Variables		Objective 24.4913	Constraints		
			Name	Nominal Value	Reliability
μ1	0.50		Abdomen_load	0.4838	1.0
μ2	1.3091		Drib_low	31.1742	0.9001
μ3	0.50		Drib_m	27.1367	0.9985
μ4	1.2942		Drib_u	29.5611	0.9983
μ5	0.8750		VC1	0.2330	1.0
μ6	1.20		VC2	0.2116	1.0
μ7	0.40		VC3	0.2896	1.0
μ8	0.3450		Pubic_F	3.9485	0.9004
μ9	0.1920		Vbp	9.2581	0.9996
			Vd	15.4671	0.9749

Note: The reliability =1.0 means that the reliability approaches closely but may not exactly equals to 1.0.

μ_w=28.4397 kg, $R_1=R_3=R_4=R_5=R_6=R_7\approx1.0$, $R_2=R_8=R_{10}=0.99865$. In this case, three constraints (Drib_low, Pubic_F and, vd) are active with the exact reliability of 0.99865. With the SORA method, three sequential cycles of optimization and reliability assessments are used. Since the desired reliability is higher than that in Case 1, the reliability analysis needs more computations. The number of function evaluations for reliability is 446, and the average number for each cycle is 149 which is larger than the one in case 1. The number of function evaluations for optimization is 84 and the total number of function evaluations is 530. The numbers of function evaluations required by the DLM_Per and the DLM_Prob are 3272 and 456195, respectively. Therefore, the SORA method is still the most efficient and the DLM_per is more efficient than the DLM_Prob.

4.2 Integrated Reliability and Robust Design for the Speed Reducer

The speed reducer problem presents the design of a simple gearbox of a small aircraft engine, which allows the engine to rotate at its most efficient speed. This has been used as a testing problem for nonlinear optimization method in the literature. The original design was modeled by Golinski (1970 and 1973) as a single-level optimization, and since then many others have used it to test a variety of methods, for example, as an artificial multidisciplinary optimization problem (Li, 1989; Datseris 1982; Azarm and Li, 1989, Renaud, 1993 and Boden and Grauer, 1995).

Since in the design of the speed reducer there are many random variables, such as the sizes of the components (gears, shafts, etc.), material properties, and operation environment (rotation speed, engine power etc.), it is also a good example for optimization under uncertainty. We modify this problem as a probabilistic design problem by assigning randomness to appropriate variables and parameters.

The deterministic design model of the speed reducer is given in Li (1989). In the probabilistic design, there are two deterministic design variables: $d_1 = m =$ teeth module, and $d_2 = z =$ number of pinion teeth, and five random design variables: $X_1 = b =$ face width, $X_2 = l_1 =$ shaft-length 1 (between bearings), $X_3 = l_2 =$ shaft-length 2 (between bearings), $X_4 = d_1 =$ shaft diameter 1, $X_5 = d_2 =$ shaft diameter 2. There are 15 random parameters $P_1 \sim P_{15}$, including the material properties, the rotation speed, and the engine power, and 11 constraints among which ten (g1~g10) are probabilistic constraints which are related to the bending condition, the compressive stress limitation, the transverse deflection of shafts and the substitute stress conditions, as well as one deterministic constraint g11. The design objective is to minimize the weight of the speed reducer.

The integrated reliability and robust design model is provided as follows:

Find $d_i,\quad i = 1, 2$ and $\mu_j,\quad j = 1, 2, \cdots, 9$

Minimize $w_1 \dfrac{\mu_w}{\mu^*_{w2}} + w_2 \dfrac{\sigma_w}{\sigma^*_w}$

Subject to $\text{Prob}\{g_k \le 0\} \ge \text{R}_\text{k} \quad k = 1, \cdots, 10$

$g_{11} \le 0$

Side Constraints:

$l_{di} \le d_i \le u_{di},\ i = 1,2$

$l_{\mu j} \le \mu_j \le u_{\mu j},\ i = 1,10$

Figure 10. Integrated Reliability and Robust Design Model

w_1 and w_2 are weighting factors. μ^*_w (obtained by $w_1 = 1$ and $w_2 = 0$) and σ^*_w (obtained by $w_1 = 0$ and $w_2 = 1$) are the ideal solutions used to normalize the two aspects in the objective, i.e., optimizing the mean performance and minimizing performance deviations.

The mean μ_w and the standard deviation of the weight σ_w are evaluated by Taylor expansion at the means of the random variables.

Since we consider the robustness in the design objective and the reliability requirements in the design feasibility, we call this design integrated reliability and robust design.

The desired reliability for all the probabilistic constraints is 0.95. All the three methods, the SORA method, the DLM_Per and the DLM_Prob, are used to solve this problem and the results from them are identical.

A comparison of the total number of function evaluations is provided in Table 3. The number of function evaluations of the SORA method is 338, among which 164 used for optimization and 174 used for reliability assessments. Three cycles are used by SORA to solve the problem. The SORA method is the most efficient method for this problem.

Table 3. Number Of Function Evaluations

Method	NFE for Reliability Assessment	NFE for Optimization	Total NFE
SORA	174	164	338
DLM_Per	–	–	3532
DLM_Prob	–	–	20134

5. DISCUSSIONS AND CONCLUSION

The purpose of developing the SORA method is to improve the efficiency of probabilistic design. Different from the existing double loop methods, the SORA method employs the strategy of sequential single loops for optimization and reliability assessment, which separates the reliability assessment from the optimization loop. The measures taken by SORA include the use of the percentile formulation for the probabilistic constraints instead of the reliability formulation to avoid evaluating the actual reliabilities; the use of sequential cycles of optimization and reliability assessments to reduce the total number of reliability analyses; and the use of an efficient and robust inverse MPP search algorithm to perform the reliability assessments.

The combination of these measures formulates a serial of “equivalent” deterministic optimization problems in such a way that the optimum solution can be identified progressively and quickly. The probabilistic constraints are formulated as the deterministic constraint functions (for R percentile evaluations), which are evaluated at their MPPs. As a result, there is no need to perform reliability assessment within each optimization. If the design objective is deterministic, such as those in reliability-based design, there is no need to perform any probabilistic analysis in the optimization process. Therefore, the SORA method is extremely efficient for reliability-based optimization. As demonstrated in Example 1, the SORA method has much higher efficiency than the double loop methods. When the objective is formulated probabilistically, for example, the design objective is related to both the mean and standard deviation of the objective function for a robust design, or the design objective is the expected utility in the utility optimization, the SORA method is still applicable. However, its efficiency depends on how to evaluate the probabilistic characteristics of the objective function. If computationally expensive methods, such as the sampling method, are employed, the efficiency will decrease. If deterministically equivalent methods are used to evaluate the probabilistic objective, the efficiency of the SORA method will still be acceptable. One example of this treatment is demonstrated by the integrated reliability and robust design for the speed reducer presented in Section 4, where we employed the Taylor expansion to evaluate the mean and the standard deviation of the objective function.

There is a potential to further improve the efficiency of the SORA method. Some of the probabilistic constraints are never active during the whole design process and their reliabilities are always above the desired levels. Therefore, it is not necessary to evaluate the percentiles of those constraints in the reliability assessment in each cycle. By investigating the method to identify the never-active probabilistic constraints can avoid unnecessary reliability assessments and hence can improve the efficiency considerably.

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