The Use of Optimization Techniques to Design Controlled Diffusion Compressor Blading

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ABSTRACT

A method is presented for automating compressor blade design using numerical optimization, and is applied to the design of a controlled diffusion stator blade row. A general purpose optimization procedure is employed, which is based on conjugate directions for locally unconstrained problems and on feasible directions for locally constrained problems. Coupled to the optimizer is an analysis package consisting of three analysis programs which calculate blade geometry, inviscid flow, and blade surface boundary layers.

The optimization concepts are briefly discussed. Selection of design objective and constraints is described. The procedure for automating the design of a two-dimensional blade section is discussed, and design results are presented.

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NOMENCLATURE

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>AC1, BC1, CC1, DC1, AC2, BC2, CC2, DC2</td>
<td>polynomial coefficients for blade angle distribution expression</td>
</tr>
<tr>
<td>AT1, BT1, CT1, DT1, AT2, BT2, CT2, DT2</td>
<td>polynomial coefficients for blade thickness distribution expression</td>
</tr>
<tr>
<td>C</td>
<td>chord</td>
</tr>
<tr>
<td>F(X)</td>
<td>objective function</td>
</tr>
<tr>
<td>Gj(X)</td>
<td>constraint functions</td>
</tr>
<tr>
<td>H1, H1,crit</td>
<td>incompressible form factor, critical value of incompressible form factor at which turbulent boundary layer separates, H1,crit = 2.0 in this study</td>
</tr>
<tr>
<td>L.E., KCS</td>
<td>leading edge of blade angle with respect to meridional direction of blade mean line midway between transition location and trailing edge</td>
</tr>
<tr>
<td>KICR</td>
<td>angle with respect to meridional direction of blade mean line at leading edge</td>
</tr>
<tr>
<td>KOCR</td>
<td>angle with respect to meridional direction of blade mean line at trailing edge</td>
</tr>
<tr>
<td>KTC</td>
<td>angle with respect to meridional direction of blade mean line at transition location</td>
</tr>
<tr>
<td>5</td>
<td>search direction</td>
</tr>
<tr>
<td>s1, s2</td>
<td>distance from transition location along mean line, front segment, rear segment</td>
</tr>
<tr>
<td>sm1, sm1e, sm2, sm2e</td>
<td>distance from maximum thickness location to blade leading edge, along mean line, rear segment, location to blade trailing edge along mean line</td>
</tr>
<tr>
<td>T</td>
<td>distance from leading edge to intersection of two polynomial segments describing mean line/chord</td>
</tr>
<tr>
<td>T.M, T.E.</td>
<td>thickness of blade, front and rear segments respectively</td>
</tr>
<tr>
<td>U, V</td>
<td>surface velocity</td>
</tr>
<tr>
<td>X</td>
<td>vector of design variables</td>
</tr>
<tr>
<td>XCHORD</td>
<td>meridional projection of blade chord</td>
</tr>
<tr>
<td>ZM</td>
<td>distance from leading edge to maximum thickness location/chord</td>
</tr>
<tr>
<td>θ*</td>
<td>move parameter</td>
</tr>
<tr>
<td>κ</td>
<td>blade angle</td>
</tr>
</tbody>
</table>

Subscripts:

1, 2, m, n, ps, ss, t | front segment, rear segment, number of constraints, number of design variables, pressure surface, suction surface, transition |

*Member ASME.
INTRODUCTION
Throughout the history of compressor technology, blade shapes have been specified by geometric families or classes. For the most part, these families have been derived from early wing shapes and improved by empiricism, or have been directly specified from simple geometric shapes such as circular arcs and parabolas.

During the past decade, computational methods for the calculation of flow through compressor blade rows have advanced substantially, as have computer speeds. With these advances has come the capability to rapidly design and analyze flow over arbitrary blade shapes. Indeed, at the present time, the analysis methods are being synthesized into computer-aided design systems. In most cases these systems are "manual", i.e., non-automated. Because of the great flexibility in choice of blade shape, the design process can become quite cumbersome and repetitive unless automated in some fashion. One of the most attractive methods for automating the design process is numerical optimization. Much progress has been made recently in bringing the technique to bear on engineering problems, particularly in the field of Aeronautics (I). Of the many numerical optimization algorithms in existence, the one used in Ref. 1 and described in Ref. 2 with its control program (3) is sufficiently general and user-oriented to be of particular interest. It is used in the work reported herein, and is coupled to analysis programs which calculate blade shape, the inviscid flow field, and the boundary layer for a two-dimensional blade section.

With the advent of arbitrary blade shapes, the concept of controlling velocity diffusion (and consequently boundary layer growth) on the suction surface has received increasing attention. In the transonic flow regime, such blading has generally been referred to as "supercritical blading" since the local supersonic flow is controlled as well as the boundary layer growth. In the subsonic regime the blading is often simply referred to as "controlled diffusion". Methods of analysis have generally been inverse, in which a velocity distribution of a general Stratford type (4) is prescribed at the outlet, and a blade shape derived from it (5 and 6).

The problem addressed in the present work is the redesign of a high-subsonic stator blade row utilizing a controlled diffusion blade shape. The analytical methods are direct rather than inverse. A blade shape is initially prescribed and aerodynamic performance calculated. Perturbations on the blade shape are effected and aerodynamic performance recalculated until specified conditions are met. The resulting velocity distributions over the suction surface of the blade are also of the general Stratford type, but in this case are controlled by constraints imposed on the geometric and aerodynamic parameters.

The subject stator row uses the same flow path and velocity triangles as the first stage stator of the NASA Two-Stage Fan (7). The original design was highly successful, showing a first stage peak adiabatic efficiency of 87.0 percent, and a remarkably low radial distribution of loss across the stator. Consequently, significant improvement in performance with controlled diffusion blading cannot be expected, nor is that the purpose of the present work. The principal objective of the work presented herein is to develop and demonstrate the feasibility of an automated design procedure based on numerical optimization. Experimental evaluation of the resulting design is planned for both a single-stage environment and a two-dimensional cascade.
Potential Flow Solution

The potential flow about the blade section in the two-dimensional, blade-to-blade plane is calculated by the method developed by Katsanis, TSONIC (9). The program solves the stream function equation by finite difference techniques for the subsonic, compressible flow regime. It is necessary to specify as input the fluid properties, inlet total temperature and density, weight flow, blade geometry, inlet and outlet flow angles, finite difference mesh, and a meridional distribution of streamtube height and total pressure loss. In the design presented herein, a linear distribution of streamtube height and estimated total loss was utilized.

Because the nature of the equations dictates that the solution be of a boundary value type, the outlet flow angle must be specified on the downstream boundary. This effectively sets the Kutta condition. Since this condition is related to one of the constraints chosen for the optimization process, its discussion will be reserved until later.

Boundary Layer Calculations

Blade surface boundary layers were calculated using the program developed by McNally (10). In addition to the surface velocities, required input includes upstream flow conditions, fluid properties, and blade surface geometry. Among the output provided by the program are the conventional boundary layer thicknesses, form factors, wall friction coefficient, and momentum thickness Reynolds number.

The program uses integral methods to solve the two-dimensional compressible laminar and turbulent boundary layer equations in an arbitrary pressure gradient. Cohen and Reshotko's method (11) is used for the laminar boundary layer, transition is predicted by the Schlichting-Ulrich-Granville method (12), and Sasman and Cresci's method (13) is used for the turbulent boundary layer.

A boundary layer which is initially laminar may proceed through normal transition to a turbulent boundary layer, or it may undergo subsonic form of laminar separation before becoming turbulent. To provide flexibility for analyzing this behavior, several program options are available to the user. The calculations may proceed from a laminar boundary layer through transition to turbulent calculations. However, if laminar separation is predicted before transition, the turbulent calculations may be started by specifying a factor by which the last calculated value of momentum thickness is multiplied (this value is commonly chosen to be 1.0 to satisfy conservation of momentum). This new momentum thickness and a value for form factor based on the last calculated momentum thickness Reynolds number are used as initial values for the turbulent calculations.

Optimization Program

The optimization algorithm in Fortran code is known as COPES, and is reported in Ref. 2. A general purpose control program known as COPES is coupled to the algorithm (3).

The general mathematical representation of a numerical optimization problem is stated as:

Minimize $\text{OBJ} = F(X)$

subject to $G_j(X) < 0, j = 1, m$

$x^L_i < x_i < x^U_i i = 1, n$

$X$ is a vector consisting of the design variables. $x^L$ and $x^U$ are the lower and upper bounds on the design variables and are referred to as side constraints. OBJ is the objective function. If the designer wishes to maximize a function, OBJ may be defined as the negative of the function. $G_j(X)$ set the constraint functions which the design must satisfy. When $G_j(X) < 0$, it is said to be inactive; when $G_j(X) > 0$, it is violated. When it is within a tolerance band about zero, it is active. $F(X)$ and $G_j(X)$ may be implicit or explicit functions of the design variables X, but must be continuous. (Note: this should be carefully considered when formulating those functions when they are calculated from finite difference solutions or at discrete stations.)

An initial design vector, $X$, is specified by the user. It may be feasible or infeasible, i.e., if it satisfies the inequalities of Eq. (3), it is feasible. If a feasible initial design can be found, it is usually more efficient to begin with it, at least for the types of problems discussed herein. An iteration process is then begun which follows the recursive relationship:

$$X^{q+1} = X^q + \alpha^q S^q$$

$q$ is the iteration number; the vector $S$ is the search direction in the n-dimensional space; and the scalar $\alpha^q$ (move parameter) defines the distance of travel in direction $S$, and is found by interpolation. The search direction $S$ is initially obtained by moving in the direction of steepest descent (negative gradient of the objective function) without violating constraints. The procedure is then repeated using a conjugate direction algorithm in determining a new search direction. Whenever a constraint is encountered, a new search direction is found using Zoutendijk's Method of Feasible Directions. An optimum has been achieved when no search direction can be found which will further reduce the objective function without violating a constraint.
OPTIMIZATION OF STATOR BLADE SECTION

Formulation of a specific optimization problem involves choice of an objective function (the quantity to be optimized), choice of constraints, and choice of design variables. In the present design problem, optimization of a two-dimensional stator blade section was performed at the 90 percent span from tip section. This location represented the most difficult design problem as measured by blade loading requirements.

Results of preliminary calculations of an initial blade shape which meets the specified velocity triangles at the 90 percent span location are shown in Figs. 2 to 4. Figure 2 shows the distribution of blade angle at the mean-line and the corresponding blade shape. Figure 3 is the surface velocity distribution along the suction surface obtained from the boundary layer calculations.

The initial blade design was essentially an arbitrary choice. The blade angle distribution and thickness distribution plots were determined by running the blade geometry program in a graphics mode. In this mode, the distributions can be generated by curvefitting through points which are input by the user. The process is therefore intuitive, and guided by experience. The only restriction to the process is the desirability, with regard to optimization theory, that the design be feasible. Note that for the initial design selected, the full viscous program was used.

A properly designed controlled diffusion blade should experience no suction surface boundary layer separation. This criterion is incorporated into the objective function. The following penalty function type of objective function proved to be the most successful.

\[ \text{OBJ} = \text{FORMAX} - \text{XSEPDX} \]  

FORMAX is the maximum incompressible form factor (H) occurring over the rear portion of the blade, and XSEPDX is the separation location of the turbulent boundary layer expressed as a proportion of chord length.

OBJ was minimized. Reducing FORMAX acts to increase the separation location, XSEPDX. Simultaneously reducing FORMAX and increasing XSEPDX acts to reduce OBJ.

Design Variables

Nine design variables have been selected, all of which describe the geometry of the blade. These variables are:

- \( T \), transition location of two mean-line polynomials;
- \( ZM \), maximum thickness location;
- \( KOCR \), the exit blade mean-line angle (deg.);
- \( AC1, BC1 \), first two coefficients of front segment mean-line polynomial;
- \( AC2, BC2, CO2, DC2 \), all four coefficients of rear segment mean-line polynomial.

The velocity triangles are fixed for the blade section, thus fixing the loading or overall velocity diffusion across the blade row. By allowing KOCR to vary, the blade camber angle is allowed to change. The leading edge and Kutta-type condition is controlled through a constraint described below.

Incidence angle is not allowed to vary. It is fixed at the value used in the original design (7) simply as a designer's preference. If it should become desirable or necessary, the incidence angle may be allowed to vary, it can easily be incorporated by including KOCR as a design variable, and retaining the same velocity triangle information.

Although the maximum thickness location, ZM, is allowed to vary, the coefficients of the blade thickness polynomial are held fixed at the values used in the preliminary (initial) blade shape, strictly as a designer's choice.

Each of the above variables is allowed to vary within user-selected limits. The upper and lower bounds for each are listed below.

<table>
<thead>
<tr>
<th>Variable</th>
<th>Lower Bound</th>
<th>Upper Bound</th>
</tr>
</thead>
<tbody>
<tr>
<td>Transition Location/Chord, T</td>
<td>.20</td>
<td>.40</td>
</tr>
<tr>
<td>Max Thickness Loc./Chord, ZM</td>
<td>.35</td>
<td>.55</td>
</tr>
<tr>
<td>Outlet Blade Angle, KOCR</td>
<td>-10</td>
<td>-2</td>
</tr>
<tr>
<td>All Coefficients</td>
<td>1.E-15</td>
<td>1.E+15</td>
</tr>
</tbody>
</table>

Constraints

Five constraint functions are specified, all being implicit functions of the design variables. Two constraints are variables calculated internally to the geometry program and control the blade angle distribution. By controlling the blade angle distribution, a controlled diffusion type shape to the surface velocity distribution can be insured.

The constraints are represented in Fig. 2(a), and are \( \text{KTC} \) and \( \text{KCS} \), which were previously described. They were allowed to vary between the following bounds:

<table>
<thead>
<tr>
<th>Variable</th>
<th>Lower Bound</th>
<th>Upper Bound</th>
</tr>
</thead>
<tbody>
<tr>
<td>KTC</td>
<td>32.0</td>
<td>46.08</td>
</tr>
<tr>
<td>KCS</td>
<td>-4.0</td>
<td>11.05</td>
</tr>
</tbody>
</table>

The remaining constraints are calculated in the inviscid flow program (9) and are described with reference to a surface velocity distribution. Since TSONIC is principally a subsonic calculation procedure, the maximum surface velocity on the suction surface is constrained to the subsonic flow regime. A search procedure locates the maximum suction surface velocity. This is non-dimensionalized by the inlet freestream velocity and the ratio is defined as the constraint. The upper bound was set to be equivalent to Mach 1 condition. The lower bound is set equal to an arbitrary, small number.

Because no boundary layer calculations are made on the pressure surface of the blade, a constraint is applied to control the velocity diffusion on the pressure surface. Preliminary calculations were made of typical blade shapes, and a pressure surface velocity diffusion \( (V, \text{max}/V, \text{min}) \) of 1.65 was deemed to be a sufficiently safe upper bound. Subsequent to the optimization calculation, the pressure surface boundary layer of the optimized blade is also calculated to verify that it was truly free from separation. The lower bound of this constraint is set equal to an arbitrary, small number.
The final constraint is chosen to set the trailing edge condition, the condition equivalent to a Kutta condition. This is also equivalent to setting deviation angle. In the present work, outlet flow angle is fixed, so whatever value is taken on by blade outlet angle, KOCR, sets deviation angle. Experience with some of the conventional families of blades, supplemented with detailed analyses permitted guidelines to be set for estimating deviation for those blade families (14). But such experience is lacking for controlled diffusion blading, which is arbitrary in shape. For conventional blading, setting the deviation angle such that the suction surface and pressure surface velocity distributions close inside the trailing edge at perhaps 85 to 90 percent of chord, was one possible means for accounting for the effect of a rounded trailing edge and boundary layer separation over the rear portion of the suction surface. For controlled diffusion blading, the object is to have no boundary layer separation. If this is accomplished, the deviation angle would be expected to be small, and there would be justification for allowing the suction surface and pressure surface velocities to close to the trailing edge, rather than closing earlier.

The constraint is defined as a non-dimensional difference between velocities on the suction and pressure surfaces at the trailing edge mesh line, and is expressed:

\[
\frac{(V_{ss} - V_{ps})}{15.24} = T.E.
\]

The denominator, 15.24, was chosen to scale the constraint to about order one. Upper bound was set at zero and lower bound at -1.25. The velocity difference at the trailing edge could vary between an upper bound of zero and a lower bound of -19.0 m/sec, thus permitting some closing inside the trailing edge.

**MODIFICATIONS OF ANALYSIS PROGRAMS**

An important requirement of the optimization method is that the objective and constraint functions by continuous functions of the design variables. This necessitated certain modifications of the analysis programs.

**Modification of Inviscid Code**

Experience with the TSONIC code has shown that calculations in the trailing edge region can be quite sensitive for some configurations. Orientation of the blade, trailing edge radius, and grid intersection points can affect surface velocity calculations at or near the trailing edge station, sometimes resulting in spurious behavior. Inaccurate trailing edge velocities will produce incorrect gradients of the trailing edge constraint described above, and possibly give misleading violations of that constraint.

The means used to avoid or reduce this tendency is to incorporate a mass injection model at the trailing edge (15). In this model, tangents are formed at the intersection of the trailing edge circle with the blade surface, and extended to the vertical grid line which forms a tangent with the trailing edge circle (Fig. 5). The "wake" is then extended downstream with an orientation determined by the downstream swirl boundary condition. Experience has shown this modeling to reduce the sensitivity of the surface velocity calculations in the trailing edge region.

**Modifications of Boundary Layer Code**

There is presently no agreement concerning the initial state of a boundary layer on a compressor stator blade in the real flow environment. Some observers have measured laminar boundary layers, while others contend that due to high inlet turbulence and unsteady effects, a laminar boundary layer cannot persist. For the purposes of this study, the question is somewhat academic. An optimization design process can be developed for either case. In the present work, the existence of a laminar boundary layer is assumed, which poses the more difficult optimization problem.

The location of laminar separation and turbulent reattachment is of crucial importance to the optimization search process. The suction surface velocity distribution provides as input to the boundary layer calculation, which ideally appears as represented in Fig. 6(a). In reality it might appear as in Figs. 6(b) and (c), due to the interface relationship of geometric variables such as blade stagger, solidity, camber distribution, thickness distribution, transition location, and maximum thickness location. Boundary layer calculations are initiated with a laminar boundary layer, which would usually persist to point A. Laminar separation, rather than normal transition, occurs there in all cases because of the steep adverse pressure gradient. Conservation of momentum is assumed through the laminar separation region, with the turbulent boundary layer reattached at the next calculating station. Turbulent separation is assumed to occur when the incompressible form factor reached a critical value.

As originally modelled, point A (Fig. 6) is identified as the station at which skin friction becomes negative. Any sensitivity to design variables can cause a discontinuous jump in point A location. This effect carries through to directly influence turbulent boundary layer separation location and the objective function. To establish a consistent and conservative criterion, the following procedure was codified. Using Lagrangian interpolation, three additional points are placed between each station in the high gradient region of the velocity vs. distance array. A search procedure is begun from the trailing edge region, and locates the maximum velocity at the beginning of the high gradient region, point B in Fig. 6. Laminar separation and turbulent reattachment is effected at point B.

In addition to the modifications discussed above, several modifications were required relating to turbulent boundary layer separation. A separation criterion common to compressor blade analyses which use integral boundary layer methods is the incompressible form factor, H. Values of 1.8 to 2.6 have been proposed and used in the past (e.g., von Doenhoff and Tetervin, Ref. 16). A value of 2.0 is somewhat conservative and, in the experience of the author, has proven to be useful. The program was modified to use 2.0 as the critical incompressible form factor.

In normal operation, when a form factor at a given station exceeds 2.0, separation is assumed to have occurred at that station. If calculation stations are 5 percent of chord apart, separation location becomes a discontinuous function, changing with distance in 5 percent jumps. To correct this,
linear interpolation is used between stations to obtain the percent chord location corresponding to $H = 2.0$.

Because of the relation between blade angle distribution and thickness distribution, the incompressible form factor function often resembles Fig. 7. A maximum form factor can be observed at C. A more conventional form factor distribution is also depicted in Fig. 7, where the maximum value is identified as D. A search procedure was added to locate the maximum form factor, formax, which is one term in the objective function.

It was observed that allowing turbulent reattachment at a momentum thickness equivalent to momentum thickness at laminar separation often resulted in initial turbulent momentum thickness Reynolds numbers less than 320, the minimum value experimentally observed for a turbulent boundary layer (17). Therefore, as a final modification, the code was altered to provide a minimum thickness equivalent to a Reynolds number of 320.

**DESIGN RESULTS**

The optimization history is shown in Fig. 8. Most improvement occurred in the first two iterations. At the end of two iterations a blade had been found with no boundary layer separation ($XSEPDX = 1.0$). Reduction of the objective function for subsequent iterations involved reduction of FORMAX only, since XSEPDX remained 1.0. All improvements beyond iteration 2 provided more safety margin from the theoretical separation condition.

CPU time on an IBM 370/3033 for the eight iterations was 49.48 minutes. A total of 85 calls on the analysis programs were made.

The initial and final blade shapes, surface velocities, and suction surface boundary layer form factor are presented and compared in Figs. 9 to 11. The pressure surface boundary layer form factor is presented in Fig. 12.

In the course of optimization, the geometric transition location moved forward from 27.3 percent of chord to 24.1, and the level of KTC (blade angle at transition) shifted downward from 36.7 degrees to 34.8 (Fig. 9). The maximum thickness location moved rearward from 48.2 percent of chord to 53.6. All polynomial coefficients describing the blade angle distribution were altered, as would be expected, since these are design variables. The polynomial coefficients describing the thickness distribution were not altered, since they were not design variables. However, since the maximum thickness location itself changed, the actual distribution of thickness was altered, as is evident from Fig. 9(b). If difficulties in achieving a satisfactory design had been experienced, the polynomial coefficients for thickness distribution could have been added as additional design variables, but at the cost of increased computing time. Outlet blade angle, KOCR, changed little during the process.

Large excursions in KOCR were prevented because it is closely related to the trailing edge constraint (Eq. (6)).

The changes effected in the surface velocities by the optimization procedure (Fig. 10) are a bit more dramatic in appearance than are the geometry changes. Peak velocity on the suction surface was reduced, as was the large velocity diffusion over the front portion of the pressure surface. The unconventional waviness of the pressure surface velocity is due to the aft location of the maximum thickness. Fitting the thickness distribution through this maximum thickness location, in combination with the forward transition location, results in a region of reversed curvature on the pressure surface near the maximum thickness location, and is evident on Fig. 9(c). The effect on the flow normal a small wavelength and other results as a small wave on the suction surface as well. Aside from the dubious aesthetic appearance, no adverse aerodynamic effects can be attributed to this behavior. The calculated boundary layers appear well-behaved, with the maximum incompressible form factor on the suction surface being 1.924, and on the pressure surface 1.780.

In completing the design of the stator, only one other blade section was optimized, the hub section at the inner endwall. This blade element will be in the wall boundary layer, so that true two-dimensional flow is not expected to exist. Resulting transition location and maximum thickness location were not greatly different from the values found at the 90 percent span location. Blade angle polynomial coefficients different from those obtained at 90 percent span were obtained. However, for reasons relating to the blade stacking procedure, which will be described below, the polynomial coefficients obtained at the 90 percent span location were used also at the 100 percent span. The resulting two-dimensional calculation for the blade with these coefficients indicated no boundary layer separation.

All other blade sections were specified based on the optimized design obtained at the 90 percent span section. Each of these blade sections, which lie on streamlines, is then radially stacked. Fabrication coordinates are interpolated at several planes parallel to the axis of rotation of the compressor. In principle, each of the blade sections on the six chosen streamlines utilized could be designed by optimization. This could and probably would result in six different sets of transition location, maximum thickness location, and blade angle polynomial coefficients. The fabrication coordinates are generated by a design point streamline curvature code. As input to this code, a radial curvefit of each of the polynomial coefficients must be provided. Transition location and maximum thickness location for each blade section are input directly. The blade coordinates on each streamline section are then generated. Finally, coordinates at the horizontal fabrication planes are obtained by interpolation, based on a cubic fit of the blade coordinates at the four streamlines most closely straddling the desired fabrication plane.

Because of the curvefitting at various stages of this process, prudence suggests avoiding the possibility of large radial variations in the design parameters. Therefore, a constant radial distribution of each parameter was sought, with one exception. Maximum thickness location was arbitrarily moved forward to 47 percent of chord for all sections between the tip and 70 percent of span from the tip. Although it was not necessary to do this, the effect was to relieve the reversed curvature condition on the pressure surface. The transition location and all polynomial coefficients were maintained at the same values obtained for the optimized 90 percent span section. At the 100 percent span section, transition and maximum thickness locations found from optimization at that section were used (0.26 and 0.52 respectively), and blade angle polynomial coefficients equivalent to those at 90 percent span were used. Thus, neither the polynomial coefficients for blade angle nor maximum thickness
varied radially. Transition location was constant from tip to 90 percent span, and differed only slightly at 100 percent span. Maximum thickness location was constant from the tip to 70 percent span at 0.47, moved rearward to 0.53 at 90 percent span, and slightly forward to 0.52 at 100 percent span. The exit blade angle, KOCR, varied only slightly from tip to hub in a range from -3.7 to -4.0. Since design exit flow angle is zero degrees for all sections, the negative value of KOCR represents deviation angle. If, indeed, the boundary layer does not separate from the blade as theoretically predicted, the deviation angles of about 4 degrees may be more realistic than they appear to be. The blade geometry and surface velocity distributions for the blade sections at midspan and 10 percent span from tip are shown in Figs. 13 and 14.

SUMMARY AND CONCLUDING REMARKS

A method has been presented for automated compressor blade design using numerical optimization techniques. The method was applied to the design of a control-diffusion stator blade row. Three analysis programs were coupled to the numerical optimization program: a blade geometry generation program which uses polynomial representation for blade angle and thickness distributions, a compressible, inviscid flow program, and an integral boundary layer program. Seven of the nine design variables were related to blade angle distribution. another located the maximum thickness of the blade, and the last controlled camber and deviation angles. Two constraint functions operated in the geometry program to produce shapes with controlled diffusion velocity distributions. Constraint functions applied in the flow analysis program limited suction surface velocities to the subsonic regime, limited the velocity diffusion on the pressure surface, and set the trailing edge condition for inviscid calculations. The objective function, which was minimized, was of a penalty function form, and effectively produced a blade whose suction surface turbulent boundary layer did not separate. The optimization procedure for the subject blade section required eight major iterations involving 85 calls on the geometry/aerodynamic analysis programs. Total CPU time on an IBM 370/3033 computer was 49.48 minutes.

When using the numerical optimization procedure, it was essential that the gradients of the constraint and objective functions be smooth and accurate. Therefore, some modifications of the analysis programs were necessary to ensure that these functions were continuous. The design problem, as formulated here, produced a blade shape which satisfied the design criteria, while holding the polynomial coefficients describing thickness distribution, the value of maximum thickness, and the incidence angle constant. The method thus still offers great flexibility for adaptation to more demanding design requirements.

REFERENCES

Figure 3. - Initial surface velocity distribution.

Figure 4. - Initial design-suction surface turbulent boundary layer form factor distribution.
Figure 5. - Mass flow injection model; TSONIC program.

Figure 6. - Representation of ideal and calculated suction surface velocities.
Figure 7. - Turbulent incompressible form factors for different classes of blades.

Figure 8. - Optimization history.
Figure 9. Comparisons of initial and final blade designs.
Figure 12. Final blade design turbulent boundary layer incompressible form factor, pressure surface.

Figure 13. Surface velocity distribution and blade shape, final blade, 50 percent span from tip.
Figure 14. - Surface velocity distribution and blade shape, final blade, 10 percent span from tip.