

T.R.A.U.P.M.  
/archibots

**BRAINSTORMING**

MODEL AS INTERFACE

**VOODOO DOLL ARCHITECTURE**

PHYSICAL  VIRTUAL  PHYSICAL

CHANGING CODE  CHANGING ARCHITECTURE  CHANGING CODE

OCCUPIED MANAGED CONTROLLED

TANGIBLE  PROGRAMMED BEHAVIOR / RECORD AND PLAY

PERSUASIVE

TESTING

MEASUREMENT + VISUALIZATION

4D DASHBOARD

**PRECEDENTS**

MANAGEMENT INTERFACES

WAR GAMING (NAPOLEON)

AUTODESK VIRTUAL CITY

4D DASHBOARD

TANGIBLE PROGRAMMING INTERFACES

SIFTABLES

TOPOBO

CKBOTS

ROBLOCKS

ARCHITECTURAL MODEL

NSF CFP

T.R.A.U.P.M.

**Tangible Recursive Architectural & Urban Planning Models**

As computationally intensive interfaces move from linguistic to objective forms, how can intelligent physical models be used to plan complex spatial systems, monitor structural performance and allow for real-time occupant driven architectural interactivity?

The promise of habitat-scale robotics allows for the design of architectural systems to continue dynamically before, during and after physical structures are put in place.

Projects should focus on theoretical and practical potential of the use of simple or advanced materials to realize fully functional model recursivity. These should include plans for physical model design, matter-code integration, tangible interactivity patterns and protocols, networked robotics to control architectural partition, sensing mechanisms to capture and display performance information.