MEC-E8001 Finite Element Analysis; Formulae

GENERAL

Displacement: $\vec{u} = u_X \vec{I} + u_Y \vec{J} + u_Z \vec{K} = u_x \vec{i} + u_y \vec{j} + u_z \vec{k} = u\vec{i} + v\vec{j} + w\vec{k}$

Rotation (small): $\vec{\theta} = \theta_X \vec{I} + \theta_Y \vec{J} + \theta_Z \vec{K} = \theta_x \vec{i} + \theta_y \vec{j} + \theta_z \vec{k} = \phi\vec{i} + \theta\vec{j} + \psi\vec{k}$

Coordinate systems: $\begin{Bmatrix} \vec{i} \\ \vec{j} \\ \vec{k} \end{Bmatrix} = \begin{bmatrix} i_X & i_Y & i_Z \\ j_X & j_Y & j_Z \\ k_X & k_Y & k_Z \end{bmatrix} \begin{Bmatrix} \vec{I} \\ \vec{J} \\ \vec{K} \end{Bmatrix}$

Stress-strain: $\begin{Bmatrix} \sigma_{xx} \\ \sigma_{yy} \\ \sigma_{zz} \end{Bmatrix} = [E] \begin{Bmatrix} \varepsilon_{xx} \\ \varepsilon_{yy} \\ \varepsilon_{zz} \end{Bmatrix}, \quad \begin{Bmatrix} \sigma_{xy} \\ \sigma_{yz} \\ \sigma_{zx} \end{Bmatrix} = G \begin{Bmatrix} \gamma_{xy} \\ \gamma_{yz} \\ \gamma_{zx} \end{Bmatrix}$

Elasticity matrices: $[C] \equiv [E], \; [C]_\sigma \equiv [E]_\sigma, \; G = \dfrac{E}{2(1+\nu)}$

$$[E] = \frac{E}{(1+\nu)(1-2\nu)} \begin{bmatrix} 1-\nu & \nu & \nu \\ \nu & 1-\nu & \nu \\ \nu & \nu & 1-\nu \end{bmatrix}, \quad [E]^{-1} = \frac{1}{E} \begin{bmatrix} 1 & -\nu & -\nu \\ -\nu & 1 & -\nu \\ -\nu & -\nu & 1 \end{bmatrix}$$

$$[E]_\sigma = \frac{E}{1-\nu^2} \begin{bmatrix} 1 & \nu & 0 \\ \nu & 1 & 0 \\ 0 & 0 & (1-\nu)/2 \end{bmatrix}, \quad [E]_\varepsilon = \frac{E}{(1+\nu)(1-2\nu)} \begin{bmatrix} 1-\nu & \nu & 0 \\ \nu & 1-\nu & 0 \\ 0 & 0 & (1-2\nu)/2 \end{bmatrix}$$

Strain-displacement: $\begin{Bmatrix} \varepsilon_{xx} \\ \varepsilon_{yy} \\ \varepsilon_{zz} \end{Bmatrix} = \begin{Bmatrix} \partial u/\partial x \\ \partial v/\partial y \\ \partial w/\partial z \end{Bmatrix}, \quad \begin{Bmatrix} \gamma_{xy} \\ \gamma_{yz} \\ \gamma_{zx} \end{Bmatrix} = \begin{Bmatrix} \partial u/\partial y + \partial v/\partial x \\ \partial v/\partial z + \partial w/\partial y \\ \partial w/\partial x + \partial u/\partial z \end{Bmatrix}$

$$\begin{Bmatrix} \mathrm{E}_{xx} \\ \mathrm{E}_{yy} \\ \mathrm{E}_{zz} \end{Bmatrix} = \begin{Bmatrix} \varepsilon_{xx} \\ \varepsilon_{yy} \\ \varepsilon_{zz} \end{Bmatrix} + \frac{1}{2} \begin{Bmatrix} (\partial u/\partial x)^2 + (\partial v/\partial x)^2 + (\partial w/\partial x)^2 \\ (\partial u/\partial y)^2 + (\partial v/\partial y)^2 + (\partial w/\partial y)^2 \\ (\partial u/\partial z)^2 + (\partial v/\partial z)^2 + (\partial w/\partial z)^2 \end{Bmatrix}$$

$$\begin{Bmatrix} \mathrm{E}_{xy} \\ \mathrm{E}_{yz} \\ \mathrm{E}_{zx} \end{Bmatrix} = \frac{1}{2} \begin{Bmatrix} \gamma_{xy} \\ \gamma_{yz} \\ \gamma_{zx} \end{Bmatrix} + \frac{1}{2} \begin{Bmatrix} (\partial u/\partial x)(\partial u/\partial y) + (\partial v/\partial x)(\partial v/\partial y) + (\partial w/\partial x)(\partial w/\partial y) \\ (\partial u/\partial y)(\partial u/\partial z) + (\partial v/\partial y)(\partial v/\partial z) + (\partial w/\partial y)(\partial w/\partial z) \\ (\partial u/\partial z)(\partial u/\partial x) + (\partial v/\partial z)(\partial v/\partial x) + (\partial w/\partial z)(\partial w/\partial x) \end{Bmatrix}$$

PRINCIPLE OF VIRTUAL WORK

$\delta W = \sum_{e\in E} \delta W^e = 0 \;\; \forall \delta \mathbf{a}$, $\delta W = \int_\Omega \delta w d\Omega$

Bar (x): $\delta w_\Omega^{\text{int}} = -\frac{\partial \delta u}{\partial x} EA \frac{\partial u}{\partial x}$, $\delta w_\Omega^{\text{ext}} = \delta u f_x$, $\delta w_\Omega^{\text{ine}} = -\delta u \rho A \frac{\partial^2 u}{\partial t^2}$, $\delta w_\Omega^{\text{cpl}} = \frac{d\delta u}{dx} EA\alpha\Delta\vartheta$

$\delta w_{\Omega^\circ}^{\text{int}} = -\delta \mathrm{E}_{xx} A^\circ C \mathrm{E}_{xx}$, $\delta w_{\Omega^\circ}^{\text{ext}} = A^\circ \rho^\circ (\delta u g_x + \delta v g_y + \delta w g_z)$

$\delta p_\Omega^{\text{int}} = -\frac{d\delta\vartheta}{dx} kA \frac{d\vartheta}{dx}$, $\delta p_\Omega^{\text{ext}} = \delta\vartheta s$

Torsion (x): $\delta w_\Omega^{\text{int}} = -\frac{\partial \delta\phi}{\partial x} GJ \frac{\partial \phi}{\partial x}$, $\delta w_\Omega^{\text{ext}} = \delta\phi m_x$, $\delta w_\Omega^{\text{ine}} = -\delta\phi \rho J \frac{\partial^2 \phi}{\partial t^2}$

Bending (xz): $\delta w_\Omega^{\text{int}} = -\frac{\partial^2 \delta w}{\partial x^2} EI_{yy} \frac{\partial^2 w}{\partial x^2}$, $\delta w_\Omega^{\text{ext}} = \delta w f_z$

$\delta w_\Omega^{\text{ine}} = -\delta w \rho A \frac{\partial^2 w}{\partial t^2} - \frac{\partial \delta w}{\partial x} \rho I_{yy} \frac{\partial^2}{\partial t^2} \frac{\partial w}{\partial x}$, $\delta w_\Omega^{\text{sta}} = -\frac{d\delta w}{dx} N \frac{dw}{dx}$ where $N = EA \frac{du}{dx}$.

Bending (xy): $\delta w_\Omega^{\text{int}} = -\frac{\partial^2 \delta v}{\partial x^2} EI_{zz} \frac{\partial^2 v}{\partial x^2}$, $\delta w_\Omega^{\text{ext}} = \delta v f_y$,

$\delta w_\Omega^{\text{ine}} = -\delta v \rho A \frac{\partial^2 v}{\partial t^2} - \frac{\partial \delta v}{\partial x} \rho I_{zz} \frac{\partial^2}{\partial t^2} \frac{\partial v}{\partial x}$, $\delta w_\Omega^{\text{sta}} = -\frac{d\delta v}{dx} N \frac{dv}{dx}$ where $N = EA \frac{du}{dx}$

Thin-slab (xy):

$$\delta w_\Omega^{\text{int}} = -\begin{Bmatrix} \partial\delta u/\partial x \\ \partial\delta v/\partial y \\ \partial\delta u/\partial y + \partial\delta v/\partial x \end{Bmatrix}^{\mathrm{T}} t[E]_\sigma \begin{Bmatrix} \partial u/\partial x \\ \partial v/\partial y \\ \partial u/\partial y + \partial v/\partial x \end{Bmatrix},\; \delta w_\Omega^{\text{ext}} = \begin{Bmatrix} \delta u \\ \delta v \end{Bmatrix}^{\mathrm{T}} \begin{Bmatrix} f_x \\ f_y \end{Bmatrix}$$

$$\delta w_{\partial\Omega}^{\text{ext}} = \begin{Bmatrix} \delta u \\ \delta v \end{Bmatrix}^{\mathrm{T}} \begin{Bmatrix} t_x \\ t_y \end{Bmatrix},\; \delta w_\Omega^{\text{ine}} = -\begin{Bmatrix} \delta u \\ \delta v \end{Bmatrix}^{\mathrm{T}} t\rho \frac{\partial^2}{\partial t^2} \begin{Bmatrix} u \\ v \end{Bmatrix},$$

$$\delta w_{\Omega^\circ}^{\text{int}} = -\begin{Bmatrix} \delta \mathrm{E}_{xx} \\ \delta \mathrm{E}_{yy} \\ 2\delta \mathrm{E}_{xy} \end{Bmatrix}^{\mathrm{T}} t[C]_\sigma \begin{Bmatrix} \mathrm{E}_{xx} \\ \mathrm{E}_{yy} \\ 2\mathrm{E}_{xy} \end{Bmatrix},\; \delta w_{\Omega^\circ}^{\text{ext}} = \begin{Bmatrix} \delta u \\ \delta v \end{Bmatrix}^{\mathrm{T}} \rho^\circ t^\circ \begin{Bmatrix} g_x \\ g_y \end{Bmatrix}$$

$$\delta w_\Omega^{\text{cpl}} = \begin{Bmatrix} \partial\delta u/\partial x \\ \partial\delta v/\partial x \end{Bmatrix}^{\mathrm{T}} \frac{E\alpha}{1-\nu} \int \Delta\vartheta dz \begin{Bmatrix} 1 \\ 1 \end{Bmatrix},\; \delta p_\Omega^{\text{int}} = -\begin{Bmatrix} \partial\delta\vartheta/\partial x \\ \partial\delta\vartheta/\partial y \end{Bmatrix}^{\mathrm{T}} tk \begin{Bmatrix} \partial\vartheta/\partial x \\ \partial\vartheta/\partial y \end{Bmatrix},\; \delta p_\Omega^{\text{ext}} = \delta\vartheta s$$

Bending (xy):

$$\delta w_{\Omega}^{\text{int}} = -\begin{Bmatrix} \partial^2\delta w/\partial x^2 \\ \partial^2\delta w/\partial y^2 \\ 2\partial^2\delta w/\partial x\partial y \end{Bmatrix}^{\mathrm{T}} \frac{t^3}{12}[E]_{\sigma} \begin{Bmatrix} \partial^2 w/\partial x^2 \\ \partial^2 w/\partial y^2 \\ 2\partial^2 w/\partial x\partial y \end{Bmatrix}, \quad \delta w_{\Omega}^{\text{ext}} = \delta w f_z$$

$$\delta w_{\Omega}^{\text{ine}} = -\begin{Bmatrix} \partial\delta w/\partial x \\ \partial\delta w/\partial y \end{Bmatrix}^{\mathrm{T}} \frac{t^3}{12}\rho\frac{\partial^2}{\partial t^2}\begin{Bmatrix} \partial w/\partial x \\ \partial w/\partial y \end{Bmatrix} - \delta w t\rho\frac{\partial^2 w}{\partial t^2}$$

$$\delta w_{\Omega}^{\text{sta}} = -\begin{Bmatrix} \partial\delta w/\partial x \\ \partial\delta w/\partial y \end{Bmatrix}^{\mathrm{T}} \begin{bmatrix} N_{xx} & N_{xy} \\ N_{xy} & N_{yy} \end{bmatrix}\begin{Bmatrix} \partial w/\partial x \\ \partial w/\partial y \end{Bmatrix} \text{ where } \begin{Bmatrix} N_{xx} \\ N_{yy} \\ N_{xy} \end{Bmatrix} = t\left[E\right]_{\sigma}\begin{Bmatrix} \partial u/\partial x \\ \partial v/\partial y \\ \partial u/\partial y + \partial v/\partial x \end{Bmatrix}$$

$$\delta w_{\Omega}^{\text{cpl}} = -\begin{Bmatrix} \partial^2\delta w/\partial x^2 \\ \partial^2\delta w/\partial y^2 \end{Bmatrix}^{\mathrm{T}} \frac{\alpha E}{1-\nu}\int z\Delta\vartheta dz\begin{Bmatrix} 1 \\ 1 \end{Bmatrix}$$

Solid:

$$\delta w_{\Omega}^{\text{int}} = -\begin{Bmatrix} \partial\delta u/\partial x \\ \partial\delta v/\partial y \\ \partial\delta w/\partial z \end{Bmatrix}^{\mathrm{T}} [E]\begin{Bmatrix} \partial u/\partial x \\ \partial v/\partial y \\ \partial w/\partial z \end{Bmatrix} - \begin{Bmatrix} \partial\delta u/\partial y + \partial\delta v/\partial x \\ \partial\delta v/\partial z + \partial\delta w/\partial y \\ \partial\delta w/\partial x + \partial\delta u/\partial z \end{Bmatrix}^{\mathrm{T}} G\begin{Bmatrix} \partial u/\partial y + \partial v/\partial x \\ \partial v/\partial z + \partial w/\partial y \\ \partial w/\partial x + \partial u/\partial z \end{Bmatrix}$$

$$\delta w_{\Omega}^{\text{ext}} = \begin{Bmatrix} \delta u \\ \delta v \\ \delta w \end{Bmatrix}^{\mathrm{T}} \begin{Bmatrix} f_x \\ f_y \\ f_z \end{Bmatrix}, \quad \delta w_{\Omega^\circ}^{\text{int}} = -\begin{Bmatrix} \delta \mathrm{E}_{xx} \\ \delta \mathrm{E}_{yy} \\ \delta \mathrm{E}_{zz} \end{Bmatrix}^{\mathrm{T}} [C]\begin{Bmatrix} \mathrm{E}_{xx} \\ \mathrm{E}_{yy} \\ \mathrm{E}_{zz} \end{Bmatrix} - \begin{Bmatrix} \delta \mathrm{E}_{xy} \\ \delta \mathrm{E}_{yz} \\ \delta \mathrm{E}_{zx} \end{Bmatrix}^{\mathrm{T}} 4G\begin{Bmatrix} \mathrm{E}_{xy} \\ \mathrm{E}_{yz} \\ \mathrm{E}_{zx} \end{Bmatrix}$$

$$\delta w_{\Omega}^{\text{cpl}} = \begin{Bmatrix} \partial\delta u/\partial x \\ \partial\delta v/\partial y \\ \partial\delta w/\partial z \end{Bmatrix}^{\mathrm{T}} \frac{E\alpha}{1-2\nu}\Delta\vartheta\begin{Bmatrix} 1 \\ 1 \\ 1 \end{Bmatrix}, \quad \delta p_{\Omega}^{\text{int}} = -\begin{Bmatrix} \partial\delta\vartheta/\partial x \\ \partial\delta\vartheta/\partial y \\ \partial\delta\vartheta/\partial z \end{Bmatrix}^{\mathrm{T}} k\begin{Bmatrix} \partial\vartheta/\partial x \\ \partial\vartheta/\partial y \\ \partial\vartheta/\partial z \end{Bmatrix}, \quad \delta p_{\Omega}^{\text{ext}} = \delta\vartheta s$$

APPROXIMATIONS (some) $u = \mathbf{N}^{\mathrm{T}}\mathbf{a}$, $\xi = \dfrac{x}{h}$

Quadratic: $\mathbf{N} = \begin{Bmatrix} N_1 \\ N_2 \\ N_3 \end{Bmatrix} = \begin{Bmatrix} 1-3\xi+2\xi^2 \\ 4\xi(1-\xi) \\ \xi(2\xi-1) \end{Bmatrix}$, $\mathbf{a} = \begin{Bmatrix} u_{x1} \\ u_{x2} \\ u_{x3} \end{Bmatrix}$ (bar)

Cubic: $\mathbf{N}=\begin{Bmatrix} N_{10} \\ N_{11} \\ \hdashline N_{20} \\ N_{21} \end{Bmatrix}=\begin{Bmatrix} (1-\xi)^2(1+2\xi) \\ h(1-\xi)^2\xi \\ \hdashline (3-2\xi)\xi^2 \\ h\xi^2(\xi-1) \end{Bmatrix}$, $\mathbf{a}=\begin{Bmatrix} u_{10} \\ u_{11} \\ \hdashline u_{20} \\ u_{21} \end{Bmatrix}(=\begin{Bmatrix} u_{z1} \\ -\theta_{y1} \\ \hdashline u_{z2} \\ -\theta_{y2} \end{Bmatrix}$ beam xz-plane bending)

Linear: $\mathbf{N}=\begin{bmatrix} 1 & 1 \\ x_1 & x_2 \end{bmatrix}^{-1}\begin{Bmatrix} 1 \\ x \end{Bmatrix}$, $\mathbf{N}=\begin{bmatrix} 1 & 1 & 1 \\ x_1 & x_2 & x_3 \\ y_1 & y_2 & y_3 \end{bmatrix}^{-1}\begin{Bmatrix} 1 \\ x \\ y \end{Bmatrix}$, $\mathbf{N}=\begin{bmatrix} 1 & 1 & 1 & 1 \\ x_1 & x_2 & x_3 & x_4 \\ y_1 & y_2 & y_3 & y_4 \\ z_1 & z_2 & z_3 & z_4 \end{bmatrix}^{-1}\begin{Bmatrix} 1 \\ x \\ y \\ z \end{Bmatrix}$

VIRTUAL WORK EXPRESSIONS $\ddot{a}\equiv\frac{d^2}{dt^2}a$

Rigid body/point force: $\delta W^{\text{ext}}=\begin{Bmatrix} \delta u_{X1} \\ \delta u_{Y1} \\ \delta u_{Z1} \end{Bmatrix}^{\mathrm{T}}\begin{Bmatrix} \underline{F}_X \\ \underline{F}_Y \\ \underline{F}_Z \end{Bmatrix}+\begin{Bmatrix} \delta\theta_{X1} \\ \delta\theta_{Y1} \\ \delta\theta_{Z1} \end{Bmatrix}^{\mathrm{T}}\begin{Bmatrix} \underline{M}_X \\ \underline{M}_Y \\ \underline{M}_Z \end{Bmatrix}$

$$\delta W^{\text{ine}}=-\begin{Bmatrix} \delta u_{x1} \\ \delta u_{y1} \\ \delta u_{z1} \end{Bmatrix}^{\mathrm{T}} m\begin{Bmatrix} \ddot{u}_{x1} \\ \ddot{u}_{y1} \\ \ddot{u}_{z1} \end{Bmatrix}-\begin{Bmatrix} \delta\theta_{x1} \\ \delta\theta_{y1} \\ \delta\theta_{z1} \end{Bmatrix}^{\mathrm{T}}\begin{Bmatrix} J_{xx}\ddot{\theta}_{x1} \\ J_{yy}\ddot{\theta}_{y1} \\ J_{zz}\ddot{\theta}_{z1} \end{Bmatrix}$$

Bar: $\delta W^{\text{int}}=-\begin{Bmatrix} \delta u_{x1} \\ \delta u_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{EA}{h}\begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix}\begin{Bmatrix} u_{x1} \\ u_{x2} \end{Bmatrix}$, $\delta W^{\text{ext}}=\begin{Bmatrix} \delta u_{x1} \\ \delta u_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{f_x h}{2}\begin{Bmatrix} 1 \\ 1 \end{Bmatrix}$

$$\delta W^{\text{ine}}=-\begin{Bmatrix} \delta u_{x1} \\ \delta u_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{\rho Ah}{6}\begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix}\begin{Bmatrix} \ddot{u}_{x1} \\ \ddot{u}_{x2} \end{Bmatrix},\quad \delta W^{\text{cpl}}=\begin{Bmatrix} \delta u_{x1} \\ \delta u_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{\alpha EA}{2}\begin{bmatrix} -1 & -1 \\ 1 & 1 \end{bmatrix}\begin{Bmatrix} \Delta\vartheta_1 \\ \Delta\vartheta_2 \end{Bmatrix}$$

$$\delta P^{\text{int}}=-\begin{Bmatrix} \delta\vartheta_1 \\ \delta\vartheta_2 \end{Bmatrix}^{\mathrm{T}}\frac{kA}{h}\begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix}\begin{Bmatrix} \vartheta_1 \\ \vartheta_2 \end{Bmatrix},\quad \delta P^{\text{ext}}=\begin{Bmatrix} \delta\vartheta_1 \\ \delta\vartheta_2 \end{Bmatrix}^{\mathrm{T}}\frac{sh}{2}\begin{Bmatrix} 1 \\ 1 \end{Bmatrix}$$

$$\delta W^{\text{int}}=-\delta h\frac{h}{h^\circ}CA^\circ\frac{1}{2}[(\frac{h}{h^\circ})^2-1],\quad \delta W^{\text{ext}}=\begin{Bmatrix} g_x\delta u_{x1}+g_y\delta u_{y1}+g_z\delta u_{z1} \\ g_x\delta u_{x2}+g_y\delta u_{y2}+g_z\delta u_{z2} \end{Bmatrix}^{\mathrm{T}}\frac{\rho^\circ A^\circ h^\circ}{2}\begin{Bmatrix} 1 \\ 1 \end{Bmatrix}$$

$$h^2=(h^\circ+u_{x2}-u_{x1})^2+(u_{y2}-u_{y1})^2+(u_{z2}-u_{z1})^2$$

Torsion: $\delta W^{\text{int}}=-\begin{Bmatrix} \delta\theta_{x1} \\ \delta\theta_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{GJ}{h}\begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix}\begin{Bmatrix} \theta_{x1} \\ \theta_{x2} \end{Bmatrix}$, $\delta W^{\text{ext}}=\begin{Bmatrix} \delta\theta_{x1} \\ \delta\theta_{x2} \end{Bmatrix}^{\mathrm{T}}\frac{m_x h}{2}\begin{Bmatrix} 1 \\ 1 \end{Bmatrix}$

$$\delta W^{\text{ine}} = -\begin{Bmatrix} \delta\theta_{x1} \\ \delta\theta_{x2} \end{Bmatrix}^{\mathrm{T}} \frac{\rho J h}{6} \begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix} \begin{Bmatrix} \ddot{\theta}_{x1} \\ \ddot{\theta}_{x2} \end{Bmatrix}$$

Bending (xz):

$$\delta W^{\text{int}} = -\begin{Bmatrix} \delta u_{z1} \\ \delta\theta_{y1} \\ \delta u_{z2} \\ \delta\theta_{y2} \end{Bmatrix}^{\mathrm{T}} \frac{EI_{yy}}{h^3} \begin{bmatrix} 12 & -6h & -12 & -6h \\ -6h & 4h^2 & 6h & 2h^2 \\ -12 & 6h & 12 & 6h \\ -6h & 2h^2 & 6h & 4h^2 \end{bmatrix} \begin{Bmatrix} u_{z1} \\ \theta_{y1} \\ u_{z2} \\ \theta_{y2} \end{Bmatrix}, \quad \delta W^{\text{ext}} = \begin{Bmatrix} \delta u_{z1} \\ \delta\theta_{y1} \\ \delta u_{z2} \\ \delta\theta_{y2} \end{Bmatrix}^{\mathrm{T}} \frac{f_z h}{12} \begin{Bmatrix} 6 \\ -h \\ 6 \\ h \end{Bmatrix}$$

$$\delta W^{\text{ine}} = -\begin{Bmatrix} \delta u_{z1} \\ \delta\theta_{y1} \\ \delta u_{z2} \\ \delta\theta_{y2} \end{Bmatrix}^{\mathrm{T}} \left(\frac{\rho I_{yy}}{30h} \begin{bmatrix} 36 & -3h & -36 & -3h \\ -3h & 4h^2 & 3h & -h^2 \\ -36 & 3h & 36 & 3h \\ -3h & -h^2 & 3h & 4h^2 \end{bmatrix} + \frac{\rho A h}{420} \begin{bmatrix} 156 & -22h & 54 & 13h \\ -22h & 4h^2 & -13h & -3h^2 \\ 54 & -13h & 156 & 22h \\ 13h & -3h^2 & 22h & 4h^2 \end{bmatrix}\right) \begin{Bmatrix} \ddot{u}_{z1} \\ \ddot{\theta}_{y1} \\ \ddot{u}_{z2} \\ \ddot{\theta}_{y2} \end{Bmatrix}$$

$$\delta W^{\text{sta}} = -\begin{Bmatrix} \delta u_{z1} \\ \delta\theta_{y1} \\ \delta u_{z2} \\ \delta\theta_{y2} \end{Bmatrix}^{\mathrm{T}} \frac{N}{30h} \begin{bmatrix} 36 & -3h & -36 & -3h \\ -3h & 4h^2 & 3h & -h^2 \\ -36 & 3h & 36 & 3h \\ -3h & -h^2 & 3h & 4h^2 \end{bmatrix} \begin{Bmatrix} u_{z1} \\ \theta_{y1} \\ u_{z2} \\ \theta_{y2} \end{Bmatrix} \text{ where } N = EA\left(\frac{u_{x2} - u_{x1}}{h}\right)$$

Bending (xy):

$$\delta W^{\text{int}} = -\begin{Bmatrix} \delta u_{y1} \\ \delta\theta_{z1} \\ \delta u_{y2} \\ \delta\theta_{z2} \end{Bmatrix}^{\mathrm{T}} \frac{EI_{zz}}{h^3} \begin{bmatrix} 12 & 6h & -12 & 6h \\ 6h & 4h^2 & -6h & 2h^2 \\ -12 & -6h & 12 & -6h \\ 6h & 2h^2 & -6h & 4h^2 \end{bmatrix} \begin{Bmatrix} u_{y1} \\ \theta_{z1} \\ u_{y2} \\ \theta_{z2} \end{Bmatrix}, \quad \delta W^{\text{ext}} = \begin{Bmatrix} \delta u_{y1} \\ \delta\theta_{z1} \\ \delta u_{y2} \\ \delta\theta_{z2} \end{Bmatrix}^{\mathrm{T}} \frac{f_y h}{12} \begin{Bmatrix} 6 \\ h \\ 6 \\ -h \end{Bmatrix}$$

$$\delta W^{\text{ine}} = -\begin{Bmatrix} \delta u_{y1} \\ \delta\theta_{z1} \\ \delta u_{y2} \\ \delta\theta_{z2} \end{Bmatrix}^{\mathrm{T}} \left(\frac{\rho I_{zz}}{30h} \begin{bmatrix} 36 & 3h & -36 & 3h \\ 3h & 4h^2 & -3h & -h^2 \\ -36 & -3h & 36 & -3h \\ 3h & -h^2 & -3h & 4h^2 \end{bmatrix} + \frac{\rho A h}{420} \begin{bmatrix} 156 & 22h & 54 & -13h \\ 22h & 4h^2 & 13h & -3h^2 \\ 54 & 13h & 156 & -22h \\ -13h & -3h^2 & -22h & 4h^2 \end{bmatrix}\right) \begin{Bmatrix} \ddot{u}_{y1} \\ \ddot{\theta}_{z1} \\ \ddot{u}_{y2} \\ \ddot{\theta}_{z2} \end{Bmatrix}$$

$$\delta W^{\text{sta}} = -\begin{Bmatrix} \delta u_{y1} \\ \delta\theta_{z1} \\ \delta u_{y2} \\ \delta\theta_{z2} \end{Bmatrix}^{\mathrm{T}} \frac{N}{30h} \begin{bmatrix} 36 & 3h & -36 & 3h \\ 3h & 4h^2 & -3h & -h^2 \\ -36 & -3h & 36 & -3h \\ 3h & -h^2 & -3h & 4h^2 \end{bmatrix} \begin{Bmatrix} u_{y1} \\ \theta_{z1} \\ u_{y2} \\ \theta_{z2} \end{Bmatrix} \text{ where } N = EA\left(\frac{u_{x2} - u_{x1}}{h}\right)$$

CONSTRAINTS

Frictionless contact: $\vec{n}\cdot\vec{u}_{\mathrm{A}} = 0$

Joint: $\vec{u}_{\mathrm{B}} = \vec{u}_{\mathrm{A}}$

Rigid body (link): $\vec{u}_{\mathrm{B}} = \vec{u}_{\mathrm{A}} + \vec{\theta}_{\mathrm{A}} \times \vec{\rho}_{\mathrm{AB}}$, $\vec{\theta}_{\mathrm{B}} = \vec{\theta}_{\mathrm{A}}$.

MATHEMATICS

Polar representation: $e^{i\alpha} = \cos\alpha + i\sin\alpha$, $\sin i\alpha = i\sinh\alpha$, $\cos i\alpha = \cosh\alpha$, $i^2 = -1$

Eigenvalue decomposition: $\mathbf{A} = \mathbf{X}\boldsymbol{\lambda}\mathbf{X}^{-1}$

Matrix function: If $\mathbf{A} = \mathbf{X}\boldsymbol{\lambda}\mathbf{X}^{-1}$, then $f(\mathbf{A}) = \mathbf{X}f(\boldsymbol{\lambda})\mathbf{X}^{-1}$

Newton's method: If $\mathbf{a} = \mathbf{a} - (\dfrac{\partial\mathbf{R}(\mathbf{a})}{\partial\mathbf{a}})^{-1}\mathbf{R}(\mathbf{a}) \equiv \mathbf{G}(\mathbf{a})$, then $\mathbf{R}(\mathbf{a}) = 0$

Taylor series: $f(x+\mathrm{a}) = \sum_{i=0}^{n} \dfrac{1}{i!}(\mathrm{a}\dfrac{d}{dx})^i f(x) + \dfrac{1}{(n+1)!} f^{(n+1)}(\underline{x})\mathrm{a}^{n+1} \quad \underline{x} \in [x, x+\mathrm{a}]$

TIME INTEGRATION (free vibrations)

Crank-Nicholson: $\begin{Bmatrix} \mathbf{a}_0 \\ \mathbf{a}_1\Delta t \end{Bmatrix}^{(i+1)} = \begin{bmatrix} \mathbf{I} & -\mathbf{I}/2 \\ \boldsymbol{\alpha}/2 & \mathbf{I} \end{bmatrix}^{-1} \begin{bmatrix} \mathbf{I} & \mathbf{I}/2 \\ -\boldsymbol{\alpha}/2 & \mathbf{I} \end{bmatrix} \begin{Bmatrix} \mathbf{a}_0 \\ \mathbf{a}_1\Delta t \end{Bmatrix}^{(i)}$, $\boldsymbol{\alpha} = \mathbf{M}^{-1}\mathbf{K}\Delta t^2$

Disc. Galerkin: $\begin{Bmatrix} \mathbf{a}_0 \\ \mathbf{a}_1\Delta t \end{Bmatrix}^{(i+1)} = \begin{bmatrix} \boldsymbol{\alpha} & \mathbf{I} - \boldsymbol{\alpha}/2 \\ -\mathbf{I} - \boldsymbol{\alpha}/2 & \boldsymbol{\alpha}/3 \end{bmatrix}^{-1} \begin{bmatrix} 0 & \mathbf{I} \\ -\mathbf{I} & -\mathbf{I} \end{bmatrix} \begin{Bmatrix} \mathbf{a}_0 \\ \mathbf{a}_1\Delta t \end{Bmatrix}^{(i)}$, $\boldsymbol{\alpha} = \mathbf{M}^{-1}\mathbf{K}\Delta t^2$