

Lecture 21

$$\therefore \frac{\delta^2 \mathcal{I}}{\delta v_i \delta v_j}(\bar{v}, \bar{k}) = \int_{\Omega} \underline{d}_i \otimes \underline{e}_3 \cdot \underline{C}(\underline{F}_c) [\underline{d}_j \otimes \underline{e}_3] dA$$

Similarly, (p. 142)

$$\frac{\delta^2 \mathcal{I}}{\delta k_j \delta v_i}(\bar{v}, \bar{k}) = \int_{\Omega} \underline{d}_i \otimes \underline{e}_3 \cdot \underline{C}(\underline{F}_c) [(\underline{d}_j \times \underline{I}_\alpha \underline{d}_\alpha) \otimes \underline{e}_3] dA,$$

and

$$\frac{\delta^2 \mathcal{I}}{\delta k_i \delta k_j}(\bar{v}, \bar{k}) = \int_{\Omega} [(\underline{d}_i \times \underline{I}_\alpha \underline{d}_\alpha) \otimes \underline{e}_3] \cdot \underline{C}(\underline{F}_c) [(\underline{d}_j \times \underline{I}_\beta \underline{d}_\beta) \otimes \underline{e}_3] dA$$

Define $\underline{\delta} \equiv x_i \underline{d}_i + y_i \underline{d}_i \times \underline{I}_\alpha \underline{d}_\alpha$ for scalars $x_i, y_i, i=1,2,3$. Then

$$\int_{\Omega} (\underline{\delta} \otimes \underline{e}_3) \cdot \underline{C}(\underline{F}_c) [\underline{\delta} \otimes \underline{e}_3] dA > 0 \quad \forall \underline{\delta} \neq \underline{0} \quad (SE)$$

$$\begin{aligned} & \int_{\Omega} ((x_i \underline{d}_i + y_i \underline{d}_i \times \underline{I}_\alpha \underline{d}_\alpha) \otimes \underline{e}_3) \cdot \underline{C}(\underline{F}_c) [(x_j \underline{d}_j + y_j \underline{d}_j \times \underline{I}_\beta \underline{d}_\beta) \otimes \underline{e}_3] dA \\ &= x_i \frac{\delta^2 \mathcal{I}}{\delta v_i \delta v_j} x_j + x_i \frac{\delta^2 \mathcal{I}}{\delta v_i \delta k_j} y_j + y_i \frac{\delta^2 \mathcal{I}}{\delta k_i \delta v_j} x_j \\ & \quad + y_i \frac{\delta^2 \mathcal{I}}{\delta k_i \delta k_j} y_j \end{aligned}$$

In matrix form, we have

Standard Euclidean inner product on \mathbb{R}^6

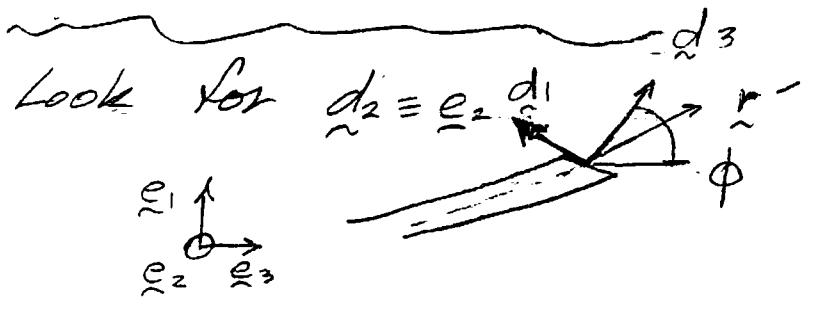
$$\left\langle \begin{pmatrix} \bar{x} \\ \vdots \\ \bar{y} \end{pmatrix}, \begin{pmatrix} \frac{\partial^2 \mathcal{Y}}{\partial \bar{v}^2}(\cdot) & \frac{\partial^2 \mathcal{Y}}{\partial \bar{v} \partial \bar{z}}(\cdot) \\ \frac{\partial^2 \mathcal{Y}}{\partial \bar{z} \partial \bar{v}}(\cdot) & \frac{\partial^2 \mathcal{Y}}{\partial \bar{z}^2}(\cdot) \end{pmatrix} \begin{pmatrix} \bar{x} \\ \vdots \\ \bar{y} \end{pmatrix} \right\rangle > 0$$

pos-defn

$$\forall \begin{pmatrix} \bar{x} \\ \vdots \\ \bar{y} \end{pmatrix} \in \mathbb{R}^6, \begin{pmatrix} \bar{x} \\ \vdots \\ \bar{y} \end{pmatrix} \neq \begin{pmatrix} 0 \\ \vdots \\ 0 \end{pmatrix}, \dots$$

i.e., the Hessian $D^2 \mathcal{Y}(\bar{v}, \bar{z})$ is positive-definite. \square

Planar Deformations



$$\hat{r}, \hat{b} \in \text{span}\{\hat{e}_1, \hat{e}_3\} \Rightarrow \hat{r}' \in \text{span}\{\hat{e}_1, \hat{e}_3\}$$

$$\hat{g} \in \text{span}\{\hat{e}_2\}$$

$$R \hat{e}_2 = \hat{e}_2$$

$$\Rightarrow \begin{cases} \underline{d}_3(s) = \cos \phi(s) \underline{e}_3 + \sin \phi(s) \underline{e}_1 \\ \underline{d}_1(s) = -\sin \phi(s) \underline{e}_3 + \cos \phi(s) \underline{e}_1 \end{cases}$$

$$\underline{d}_3' = \phi' \overbrace{(-\sin \phi \underline{e}_3 + \cos \phi \underline{e}_1)}^{\underline{d}_1} = \phi' \underline{e}_2 \times \underline{d}_3$$

$$\underline{d}_1' = -\phi' \overbrace{(\cos \phi \underline{e}_3 + \sin \phi \underline{e}_1)}^{\underline{d}_3} = \phi' \underline{e}_2 \times \underline{d}_1$$

$$\Rightarrow \underline{\kappa} = \phi' \underline{e}_2 = \phi' \underline{d}_2 \Rightarrow \kappa_2 = \phi', \quad \kappa_1 = \kappa_3 = 0$$

$$\text{Write } \underline{r}' = \xi \underline{d}_3 + \eta \underline{d}_1$$

$$\Rightarrow \nu_1 = \eta, \quad \nu_2 = 0, \quad \nu_3 = \xi$$

Exercise (23) For an isotropic, homogeneous (flip symmetric) rod, we have the free-energy representation (p. 161)

$$\mathcal{N}(\underline{\nu}, \underline{\kappa}) = \mathcal{F}_+ \left(\nu_1^2 + \nu_2^2, \kappa_1^2 + \kappa_2^2, \kappa_3^2, (\nu_1 \kappa_1 + \nu_2 \kappa_2)^2, (\nu_1 \kappa_1 + \nu_2 \kappa_2) \kappa_3, \nu_3 \right).$$

For a planar deformation, as above ($\kappa_1 = \kappa_3 = \nu_2 = 0$) show that

$$\underline{n} = \nu \underline{d}_1 + N \underline{d}_3$$

$$\underline{m} = M \underline{e}_2$$

i.e., show that $n_2 = \frac{\partial \mathcal{N}}{\partial \nu_2} \Big|_{\kappa_1 = \kappa_3 = \nu_2 = 0} = 0$ and

$$m_\alpha = \frac{\partial \mathcal{N}}{\partial \kappa_\alpha} \Big|_{\kappa_1 = \kappa_3 = \nu_2 = 0} = 0, \quad \alpha = 1, 3.$$

Recall for equilibrium we require (pp. 126, 129)

$$(*) \begin{cases} \underline{\hat{n}}' + \underline{\hat{b}} = \underline{0}, \\ \underline{m}' + \underline{r}' \times \underline{n} + \underline{\hat{g}} = \underline{0}. \end{cases}$$

$$\begin{aligned} \underline{\hat{n}}' &= V' \underline{d}_1 + V \underline{d}_1' + N' \underline{d}_3 + N \underline{d}_3' \\ &= V' \underline{d}_1 + V (-\phi' \underline{d}_3) + N' \underline{d}_3 + N \phi' \underline{d}_1 \\ &= (V' + N \phi') \underline{d}_1 + (N' - V \phi') \underline{d}_3 \end{aligned}$$

$$\underline{r}' \times \underline{n} = (\eta \underline{d}_1 + \xi \underline{d}_3) \times (V \underline{d}_1 + N \underline{d}_3) = (\xi V - \eta N) \underline{d}_2$$

Finally we assume $\underline{\hat{b}} = \hat{b}_1 \underline{d}_1 + \hat{b}_3 \underline{d}_3$, $\underline{\hat{g}} = \hat{g} \underline{e}_2$.

$$\therefore (*) \Rightarrow \begin{cases} V' + N \phi' + \hat{b}_1 = 0 \\ N' - V \phi' + \hat{b}_3 = 0 \end{cases}$$

$$(**) \quad M' + \xi V - \eta N + \hat{g} = 0$$

Constitutive hypotheses:

1. Unconstrained: $\mathcal{I}(\xi, \eta, K)$ $\hookrightarrow \phi'$

$$N = \frac{\partial \mathcal{I}(\cdot)}{\partial \xi}, \quad V = \frac{\partial \mathcal{I}(\cdot)}{\partial \eta}, \quad M = \frac{\partial \mathcal{I}(\cdot)}{\partial K}.$$

2. Unshearable: $\eta \equiv 0$ (constraint)
 $\mathcal{I}(\xi, K)$, V basic unknown

3. Inextensible: $\xi \equiv 1$ (constraint)

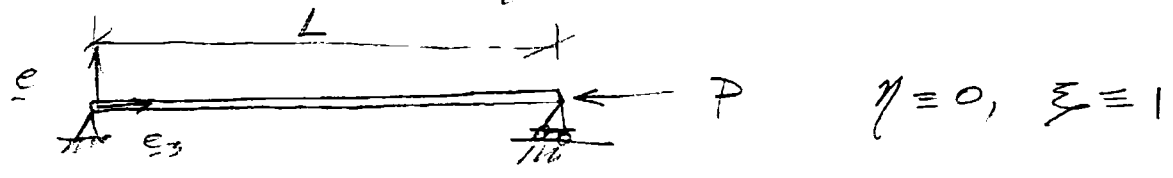
$\mathcal{I}(\eta, \kappa)$, N basic unknown

4. Unshearable, inextensible: $\eta \equiv 0, \xi \equiv 1$
(constraints)

$\mathcal{I}(\kappa)$, V, N basic unknowns

Classical case $\mathcal{I} = \frac{1}{2} EI \kappa^2$ (used by Euler 1744)

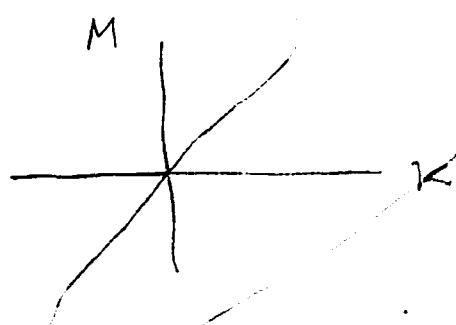
Ex | Column Buckling (Material Model 4)



$$M = \frac{d\mathcal{I}}{d\kappa}(\kappa) \equiv \hat{M}(\kappa)$$

straight - slope
"stress-free"

① $\Rightarrow \hat{M}(0) = 0$



moment curvature relation

Properties of $\hat{M}(\cdot)$

② If we return to the representation for isotropic (homogeneous) rods, p168, for this one plane, constrained rod, we have

$$\mathcal{I}(\kappa) = \frac{1}{2} EI \kappa^2, \text{ and}$$

$$\mathcal{I}'(k) = 2\hat{\Sigma}'(k^2)k \equiv \hat{M}(k)$$

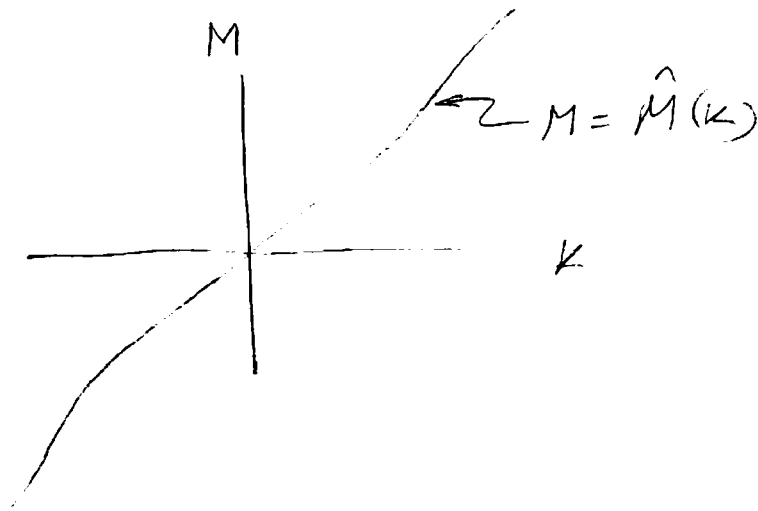
Observe: that $\hat{M}(\cdot)$ is odd.

(3) Returning to "echo" of strong ellipticity in rod theory, pp. 160-162, we see that

$$\frac{d^2 \mathcal{I}}{dk^2}(k) = \hat{M}'(k) > 0 \quad \text{monotone increasing}$$

(4) Finally, it is reasonable to assume

$$\lim_{L \rightarrow \infty} \hat{M}(L) = \infty \quad \text{growth condition}$$



Boundary conditions:

$$\underline{r}(0) = \underline{0}, \quad M(0) = 0$$

$$\underline{e}_1 \cdot \underline{r}(L) = 0, \quad \underline{n}(L) \cdot \underline{e}_3 = -P, \quad M(L) = 0$$

Our governing equations (for equilibrium) are
 (***) p. 169 for zero body force and body couple.

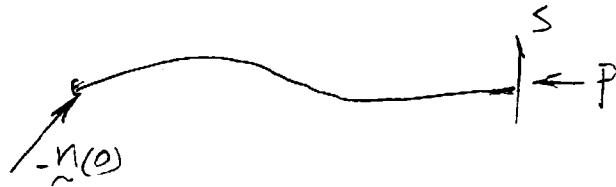
However, we can simplify things by first considering (*),

$$\underline{\hat{n}}' = \underline{0} \Rightarrow \underline{\hat{n}} = \underline{c} \text{ (const)}$$

Write $\underline{\hat{n}}(L) = S \underline{e}_1 - P \underline{e}_3$ $\leftarrow \underline{\hat{n}}(L) \cdot \underline{e}_3 = -P$

We then return to AME on p. 129 applied to the entire rod:

$$\left(\underline{r} \times \underline{\hat{n}} + \underline{m} \right) \Big|_0^L = \underline{0} \quad \text{balance of moments}$$



From the b.c.'s $\underline{m}(0) = \underline{m}(L) = \underline{0}$ and $\underline{r}(0) = \underline{0}$.

$$\therefore \underline{e}_3 \times (S \underline{e}_1 - P \underline{e}_3) = \underline{0}$$

$$\Leftrightarrow S \underline{e}_1 = \underline{0} \quad \text{for } l \neq 0$$

$$\Rightarrow \boxed{S = 0}$$

$$\Rightarrow \underline{\hat{n}}(L) = -P \underline{e}_3$$

$$\Rightarrow \underline{\hat{n}} \equiv -P \underline{e}_3$$

$$\therefore \underline{\hat{n}} = V \underline{d}_1 + N \underline{d}_3 = -P \underline{e}_3$$

$$\text{or } V(-\sin \phi \underline{e}_3 + \cos \phi \underline{e}_1) + N(\cos \phi \underline{e}_3 + \sin \phi \underline{e}_1) = -P \underline{e}_3$$

$$\Rightarrow N \cos \phi - V \sin \phi = -P$$

$$N \sin \phi + V \cos \phi = 0$$

$$\Rightarrow N = -P \cos \phi, \quad V = P \sin \phi$$

Also $(**), p. 167$

$$M' + V = 0$$

$$\therefore M' + P \sin \phi = 0$$

$$\therefore \frac{d}{ds} (\hat{M}(\phi')) + P \sin \phi = 0$$

$$(*) \quad \frac{d\hat{M}(\phi')}{ds} \phi'' + P \sin \phi = 0$$

$$M(0) = M(L) = 0 \Rightarrow \begin{cases} \hat{M}(\phi'(0)) = 0 \Leftrightarrow \phi'(0) = 0 \\ \hat{M}(\phi'(L)) = 0 \Leftrightarrow \phi'(L) = 0 \end{cases}$$

2-point boundary value problem

Note $\underline{r}' = \underline{d}_3 = \cos \phi \underline{e}_3 + \sin \phi \underline{e}_1$

$$\underline{r}(0) = \underline{r}_0, \quad \underline{e}_1 \cdot \underline{r}(L) = 0 \quad \text{decoupled from } (*)$$

Trivial solution $\phi \equiv 0$ for all P
(straight state)

Linearize about $\phi \equiv 0$: $\phi(s) \rightarrow 0 + \alpha h(s)$

$$\frac{d}{ds} \left\{ \frac{d\hat{M}}{ds}(\alpha h') [\alpha h''] + P \sin(\alpha h) \right\} \Big|_{\alpha=0} = 0$$