Table of Contents

Preface xvii

Part 1. Level 1 1

Chapter 1. The Basics of Linear Elastic Behavior 3

1.1. Cohesion forces. 4
1.2. The notion of stress 6
1.2.1. Definition 6
1.2.2. Graphical representation 7
1.2.3. Normal and shear stresses. 8
1.3. Hooke's law derived from a uniaxially applied force 9
1.3.1. The stretch test 9
1.3.2. Linear mechanical behavior 12
1.3.3. Elastic mechanical behavior 12
1.3.4. Interpretation of the test at a macroscopic level. 13
1.3.5. Interpretation of the test at a mesoscopic level 13
1.3.6. Interpretation of the test at a microscopic level 16
1.3.7. Summary. 18
1.4. Plane state of stresses 20
1.4.1. Definition 20
1.4.2. Behavior relationships for state of plane stresses 22
1.4.2.1. Case 1: simple tension along $\vec{x}$ 22
1.4.2.2. Case 2: simple tension along $\vec{y}$ 24
1.4.2.3. Case 3: pure shear 25
1.4.2.4. Complete state of stress (superposition) 28
1.4.3. Summary. 35
1.5. Particular case of straight beams. 36
1.5.1. Preliminary observations 36

1.5.1.1. Geometric characteristics 36
1.5.1.2. Resultant force and moment for cohesion forces 36
1.5.2. Effects linked to the resultant forces and moments 38
1.5.2.1. Normal resultant 40
1.5.2.2. Shear resultant $\mathcal{T}_y$ 42
1.5.2.3. Shear resultant $\mathcal{T}_z$ 43
1.5.2.4. Torsion moment $\mathcal{M}t$ 45
1.5.2.5. Bending moment $\mathcal{M}f_y$ 46
1.5.2.6. Bending moment $\mathcal{M}f_z$ 48

Chapter 2. Mechanical Behavior of Structures: An Energy Approach 51

2.1. Work and energy 51
2.1.1. Elementary work developed by a force 51
2.1.2. Elementary work developed by a moment 52
2.2. Conversion of work into energy 53
2.2.1. Potential energy of deformation 53
2.2.2. Potential energy for a spring 55
2.3. Some standard expressions for potential deformation energy 58
2.3.1. Deformation energies in a straight beam 58
2.3.1.1. Traction (or compression). 58
2.3.1.2. Torsion 61
2.3.1.3. Pure bending (xy plane) 65
2.3.1.4. Plane bending (xy plane) 69
2.3.2. Deformation energy under plane stresses. 74
2.3.2.1. Case 1: dF_x (Figure 2.17) 74
2.3.2.2. Case 2: dF_x then dF_y (Figure 2.18). 75
2.3.2.3. Case 3: dF_x then dF_y followed by dF_{xy} (Figure 2.19) 76
2.3.2.4. Different expressions for potential energy: quadratic forms. . . 77
2.4. Work produced by external forces on a structure 81
2.4.1. Beam under plane bending subjected to two forces. 82
2.4.1.1. Example 1 82
2.4.1.2. Example 2 93
2.4.2. Beam in plane bending subject to “n” forces 99
2.4.3. Generalization to any structure. 103
2.4.3.1. Structure loaded by two forces $\overrightarrow{F_1}$ and $\overrightarrow{F_2}$ 103
2.4.3.2. Structure loaded by “n” forces $\overrightarrow{F_1}$,… $\overrightarrow{F_n}$ 105
2.4.3.3. A search for real displacements on a loaded structure 107
2.4.4. Summary. 112
2.5. Links of a structure with its surroundings 113
2.5.1. Example 113

2.5.2. Generalization 118
2.5.2.1. Structures with rigid-body movements 118
2.5.2.2. “Properly linked” structure 119
2.6. Stiffness of a structure 119
2.6.1. Preliminary note 119
2.6.2. Stiffness matrix 121
2.6.3. Examples 121
2.6.3.1. Example: beam under plane bending loaded by two forces . . . 121
2.6.3.2. Example: beam under plane bending loaded by a force and a moment 123
2.6.3.3. Generalization. 125
2.6.4. Influence of the positioning. 125
2.6.4.1. Example: bar working under traction-compression 125
2.6.4.2. Example: stiffness matrix of a beam structure under plane bending. 129
2.6.4.3. Isostatism and hyperstatism. 135
2.6.5. Deformation energy and stiffness matrix 139
2.6.5.1. Example: beam from section 2.6.3.1 139
2.6.5.2. Generalization. 140

Chapter 3. Discretization of a Structure into Finite Elements. 143

3.1. Preliminary observations 143
3.1.1. Problem faced. 143
3.1.2. Practical obtaining of the deformation energy for a complex structure 144
3.1.3. Local and global coordinates 147
3.1.3.1. Definition 147
3.1.3.2. Application to the elements of the structure 149
3.1.3.3. Summary. 152
3.2. Stiffness matrix of some simple finite elements. 153
3.2.1. Truss element loaded under traction (or compression) 153
3.2.1.1. Summary: pure traction (or compression) exerted on a beam. . 153
3.2.1.2. Stiffness matrix 153
3.2.1.3. Beam element under torsion 160
3.2.1.4. Torsion loading on a beam element 161
3.2.1.5. Stiffness matrix 161
3.2.3. Beam element under plane bending 168
3.2.3.1. Summary: plane bending of a beam 168
3.2.3.2. Stiffness matrix 168
3.2.4. Triangular element for the plane state of stresses 178
3.2.4.1. Preliminary comment 178
3.2.4.2. Definition of the element 178

3.2.4.3. Form of the displacement functions 179
3.2.4.4. Determination of the stiffness matrix 181
3.2.4.5. Example 184
3.2.4.6. Performance improvement of the element 187
3.2.4.7. Summary 189
3.3. Getting the global stiffness matrix of a structure 191
3.3.1. Objective 191
3.3.2. Mechanism of the assembly of elementary matrices 191
3.3.2.1. Example 1 191
3.3.2.2. Example 2 198
3.3.1. Introduction 201
3.4. Resolution of the system $\{F\} = [K] \bullet \{d\}$ 203
3.4.1. Linkage conditions 203
3.4.2. Generalization of the method 205
3.5. Different types of finite elements available in industrial software 207

Chapter 4. Applications: Discretization of Simple Structures 209

4.1. Stiffness matrix of a spring 209
4.1.1. Helical spring 209
4.1.2. Spiral spring 211
4.2. Assembly of elements 213
4.2.1. Example 1 213
4.2.2. Example 2 217
4.2.3. Example 3 222
4.2.4. Assembly of a truss element and a beam element under simple plane bending 228
4.3. Behavior in the global coordinate system 232
4.3.1. Plane assembly of two truss elements 232
4.4. Bracket 246
4.4.1. Objectives 246
4.4.2. Modelizing 247
4.4.2.1. Definition of the beam element 247
4.4.2.2. Model using wires 248
4.4.2.3. Geometric properties of the beams 249
4.4.2.4. Support conditions 251
4.4.2.5. Loading 251
4.4.3. Calculation of the elementary stiffness matrix in the global system . 252
4.4.4. Assembly of the global stiffness matrix $[K]_{str}$ 256
4.4.5. Establishing the linkage and loading conditions 259
4.4.6. Resolution of the linear system $\{F\}_{str} = [K]_{str} \bullet \{d\}_{str}$ 260
4.4.7. Additional study of the behavior of the bracket 262
4.4.7.1. Internal linking forces on each of the isolated elements 262

4.4.7.2. Normal stresses 265
4.4.8. Using computing software 267

Part 2. Level 2 269

Chapter 5. Other Types of Finite Elements 271

5.1. Return to local and global coordinate systems. 271
5.1.1. Transfer matrix 271
5.1.2. Summary. 273
5.2. Complete beam element (any loading case) 274
5.2.1. Preliminary comments. 274
5.2.2. Obtaining the stiffness matrix in the local coordinate system. 276
5.2.3. Improvement in performances of this beam element 283
5.2.3.1. Supplementary deformation due to the shear 283
5.2.3.2. Combination of bending and torsion 285
5.2.4. Summary. 288
5.3. Elements for the plane state of stress 291
5.3.1. Triangular element 291
5.3.1.1. Preliminary comments. 291
5.3.1.2. Summary. 292
5.3.2. Quadrilateral element in plane state of stress 295
5.3.2.1. Rectangular element 295
5.3.2.2. Quadrilateral element 298
5.3.2.3. Summary. 298
5.4. Plate element 300
5.4.1. Preliminary notes. 300
5.4.2. Resultant forces and moments for cohesion forces 302
5.4.3. Plate element in bending 305
5.4.3.1. Rectangular element 305
5.4.3.2. Triangular element 308
5.4.4. Complete plate element 310
5.5. Elements for complete states of stresses 315
5.5.1. Preliminary notes. 315
5.5.2. Solid tetrahedric element 318
5.5.3. Solid parallelepipedic element 321
5.6. Shell elements. 327
5.6.1. Preliminaries 327
5.6.2. Specific case of axisymmetric shells 328
5.6.3. Axisymmetric shell element with axisymmetric boundaries 329

Chapter 6. Introduction to Finite Elements for Structural Dynamics 331

6.1. Principles and characteristics of dynamic study 332
6.1.1. Example 1 332
6.1.1.1. Description of motion 332
6.1.1.2. Dynamic behavior relation 333
6.1.1.3. Elastic behavior relation. 333
6.1.1.4. Equation of motion. 334
6.1.2. Example 2 338
6.1.2.1. Dynamic behavior relation 338
6.1.2.2. Elastic behavior relation. 339
6.1.2.3. Equations of motion 340
6.1.2.4. Eigenmodes of vibration 340
6.2. Mass properties of beams 346
6.2.1. Finite beam element in dynamic bending plane 346
6.2.2. Discretization of a beam for dynamic bending 350
6.2.3. Other types of dynamic behaviors of a beam 357
6.2.3.1. Truss element in dynamic tension-compression. 357
6.2.3.2. Beam element with circular cross-section in dynamic torsion 359
6.3. Generalization. 363
6.4. Summary. 364

Chapter 7. Criteria for Dimensioning. 365

7.1. Designing and dimensioning 365
7.2. Dimensioning in statics 370
7.2.1. The two types of criteria 370
7.2.2. Elasticity limit criterion 373
7.2.2.1. Intrinsic surface. 373
7.2.2.2. Complete state of stresses. 375
7.2.2.3. Von Mises criterion 376
7.2.3. Non-rupture criterion 382
7.2.3.1. Brittle materials. 382
7.2.3.2. Elastoplastic materials. 383
7.3. Dimensioning in fatigue. 393
7.3.1. Fatigue phenomenon. 393
7.3.2. Fatigue test 394
7.3.3. Modeling of the fatigue 397
7.3.3.1. Modeling of dynamic loading 397
7.3.3.2. Corresponding fatigue test 398
7.3.4. Estimation of fatigue strength 399
7.3.4.1. Case of a simple wavy load. 399
7.3.4.2. Case of multiple wavy loads 402

Chapter 8. Practical Aspects of Finite Element Modeling 407

8.1. Use of finite element software 407
8.1.1. Introduction 407
8.1.2. Summary tables of the properties of elements. 408
8.1.3. Connection between elements of different types 415
8.1.3.1. Introduction 415
8.1.3.2. Example 1 416
8.1.3.3. Example 2 417
8.1.3.4. Example 3 418
8.1.3.5. Conclusion. 419
8.1.4. Other practical aspects. 420
8.1.4.1. Symmetric structures 421
8.1.4.2. “Floating” models 421
8.1.4.3. Modeling of fabricated welded structures 426
8.1.4.4. “Nonlinear geometric” behavior 429
8.2. Example 1: machine-tool shaft. 432
8.2.1. Simulation exercise 432
8.2.2. Data. 433
8.2.3. Successive steps of modeling. 434
8.2.3.1. Definition of the loading 434
8.2.3.2. Linkings of the structure at boundaries 435
8.2.3.3. Finite element discretization of shaft (2) 437
8.3. Example 2: thin-walled structures 440
8.3.1. Model based on beam elements 441
8.3.1.1. Methodology 441
8.3.1.2. Junctions of centerlines 442
8.3.1.3. Relieving of linkings. 444
8.3.2. Model in plate elements 448
8.3.3. Model in beam and plate elements 449
8.4. Example 3: modeling of a massive structure. 450
8.4.1. Problem 450
8.4.2. Steps of modeling 451
8.4.2.1. Structural parts 451
8.4.2.2. Choosing the type of finite element 451
8.4.2.3. Forces applied on the body 451
8.4.2.4. Boundary conditions 452
8.4.2.5. Taking symmetries into account 454
8.4.2.6. Other aspects of the modeling 455
8.4.3. Comments on the validity of the model. 456
8.5. Summary of the successive modeling steps 457
8.5.1. Preliminary analysis 457
8.5.2. Model verification and validation 458

8.5.2.1. Before calculation 458
8.5.2.2. After calculation 459
8.5.3. Corresponding use of the software 460

Part 3. Supplements 463

Chapter 9. Behavior of Straight Beams. 465

9.1. The “straight beam” model 466
9.1.1. Definition 466
9.1.2. Main or “principal” axis of a cross-section 466
9.1.3. Applied loadings 468
9.1.4. Cohesion force and moment on a current cross-section 469
9.1.4.1. Equilibrium of the beam. 470
9.1.4.2. Defining the resultant force and moment for cohesion forces. . 471
9.1.4.3. Projections of cohesive resultant force and moment on local axis. 471
9.1.5. Hypothesis of the beam theory 474
9.1.5.1. Hypothesis on stresses. 474
9.1.5.2. Hypothesis on deformations 478
9.1.6. Microscopic equilibrium 479
9.2. Mesoscopic equilibrium or equilibrium extended to a whole cross-section 482
9.3. Behavior relations and stresses. 486
9.3.1. Normal resultant 486
9.3.1.1. Definition 486
9.3.1.2. Deformation of an elementary slice of beam. 487
9.3.1.3. Stresses on a cross-section 488
9.3.2. Torsional loading. 490
9.3.2.1. Definition 490
9.3.2.2. Deformation of an elementary beam slice 491
9.3.2.3. Simple case of a circular section. 492
9.3.2.4. Case of a non-circular cross-sectional shape. 495
9.3.2.5. Torsion characteristics for some particular cross-sectional shapes 510
9.3.2.6. Torsion with constrained warping 513
9.3.3. Pure bending 514
9.3.3.1. Pure bending in the specific case of a beam with a plane of symmetry 514
9.3.3.2. The general case of pure bending 525
9.3.4. Plane bending with shear resultant 530
9.3.4.1. Definition 530
9.3.4.2. Displacement field 531

9.3.4.3. Analysis of displacement $\eta(x, y, z)$ 534
9.3.4.4. Shear stresses 537
9.3.4.5. Behavior relation for the shear resultant 538
9.3.4.6. Application: case of a rectangular section 541
9.3.4.7. Values of the shear coefficient k_y and shear section S_{ry} for some section shapes 543
9.3.4.8. Summary. 545
9.3.5. Any loading 549
9.4. Application: example of detailed calculation of the resultant forces and moments of cohesive forces 551
9.4.1. Preliminary static analysis 551
9.4.2. Resultant force and moment on every cross-section 553

Chapter 10. Additional Elements of Elasticity 563

10.1. Reverting to the plane state of stresses 563
10.1.1. Influence of the coordinate system. 563
10.1.2. Principal directions and stresses 566
10.1.3. Mohr graphical representation 568
10.1.4. Summary 575
10.1.5. Some remarkable plane states of stresses with their Mohr representation. 576
10.1.5.1. Case 1. 576
10.1.5.2. Case 2. 577
10.1.5.3. Case 3. 581
10.1.5.4. Case 4: cylindrical vessel under pressure 582
10.1.5.5. Numerical example 586
10.1.6. Experimental evaluation of deformations to define stresses 588
10.1.7. Deformation energy in principal axes 593
10.2. Complete state of stresses 593
10.2.1. Principal directions and stresses 593
10.2.2. Stresses in any $\vec{x}$, $\vec{y}$, $\vec{z}$ axes 594
10.2.3. Deformations 597
10.2.4. Behavior relations 599
10.2.5. Strain potential energy 604
10.2.6. Summary 609
10.2.7. Components of the strain potential energy 612
10.2.7.1. Strain energy without distortion 612
10.2.7.2. Distortion strain energy 616
10.2.7.3. Summary 617

Chapter 11. Structural Joints 619

11.1. General information on connections by means of cylindrical fasteners . 620
11.1.1. Contact pressure 620
11.1.2. General information on riveting 622
11.1.2.1. Transmission of mechanical loads in riveted joints 622
11.1.2.2. Functioning of a rivet 623
11.1.3. General information on bolted joints 624
11.1.3.1. Transmission of mechanical loads in a bolted joint 624
11.1.3.2. Functioning of threaded fasteners 625
11.1.4. Deterioration of riveted and bolted joints 626
11.1.4.1. Rupture of fasteners 626
11.1.4.2. Bearing 627
11.1.4.3. Spacing of fasteners 629
11.2. Bolted joint 631
11.2.1. Simplified case where the tightening is neglected 631
11.2.1.1. Hypotheses 631
11.2.1.2. Model of joining interface 634
11.2.1.3. Forces on each fastener 637
11.2.1.4. Resistance criteria. 648
11.2.1.5. Summary 649
11.2.1.6. Example 651
11.2.2. Case of pre-tightening 654
11.2.2.1. Tightening torque 654
11.2.2.2. Behavior of a bolted joint with pre-tightening 655
11.2.2.3. Summary 663
11.2.2.4. Example 665
11.3. Riveted joint 666
11.3.1. Hypotheses. 666
11.3.2. Characteristics of the modeled joining interface. 666
11.3.3. Forces on each attachment 667
11.3.4. Graphic representation of the shear stresses 668
11.3.5. Summary 670
11.4. Welded joints 671
11.4.1. Preliminary observations and hypotheses. 671
11.4.1.1. State of stresses in a weld bead 671
11.4.1.2. Dimensioning criterion. 672
11.4.2. Determination of the stresses in the weld bead cross-section 673
11.4.2.1. Statutory aspect 673
11.4.2.2. Definition of a model for the dimensioning of a weld interface 679
11.4.2.3. Stresses on each "equivalent" bead 680
11.4.2.4. Stresses σ_n, τ_ℓ, τ_t in the bead cross-sections 683

11.4.3. Summary 686
11.4.4. Example 688

Chapter 12. Mathematical Prerequisites 691

12.1. Matrix calculus 691
12.1.1. General information 691
12.1.1.1. Definition of a matrix 691
12.1.1.2. Symmetric matrix 692
12.1.1.3. Transposition of a matrix [a] 692
12.1.2. Matrix operations 692
12.1.2.1. Addition of two matrices 692
12.1.2.2. Product of a matrix by a scalar 694
12.1.2.3. Product of two matrices 694
12.1.2.4. Inverse of a matrix 695
12.1.3. Quadratic form 696
12.1.4. Eigenvalues and eigenvectors of a matrix 697
12.1.4.1. Eigenvalues 697
12.1.4.2. Eigenvectors 697
12.2. Change in orthonormal coordinate system 698
12.2.1. Case of coplanar coordinate systems 698
12.2.2. Cases of any general coordinate systems 699

Appendix A. Modeling of Common Mechanical Joints 703

A.1. Definition 703
A.1.1. Monolithic unit. 703
A.1.2. Joints. 703
A.1.3. Perfect joints 704
A.2. Common standardized mechanical joints (ISO 3952) 704

Appendix B. Mechanical Properties of Materials 711

B.1. Mechanical properties of some materials used for structures 711
B.1.1. Steels and casting 711
B.1.2. Non-ferrous metals 712

Appendix C. List of Summaries 713

Bibliography 717