

in (a) and (17-131):

$$\begin{aligned}\Pi_p &= V + (\bar{\mathbf{P}}_{I,1}^T - \bar{\mathbf{P}}_1^T)(\mathbf{B}\mathbf{U} + \mathbf{H}_3) \\ V &= \frac{1}{2}(\mathcal{V} - \mathcal{V}_0)^T \mathbf{k}'(\mathcal{V} - \mathcal{V}_0) \\ \mathcal{V} &= \mathbf{A}_1 \mathbf{B}\mathbf{U} + \mathbf{A}_1 \mathbf{H}_3 + \mathbf{A}_2 \bar{\mathbf{U}}_2\end{aligned}\quad (17-132)$$

The variation of  $\Pi_p$  considering  $\mathbf{U}$  as the independent variable is

$$\begin{aligned}d\Pi_p &= \Delta \mathbf{U}^T [\mathbf{B}^T(\bar{\mathbf{P}}_{I,1} - \bar{\mathbf{P}}_1) + (\mathbf{B}^T \mathbf{A}_1^T \mathbf{k}' \mathbf{A}_1 \mathbf{B})\mathbf{U} \\ &\quad + \mathbf{B}^T \mathbf{A}_1^T \mathbf{k}'(\mathbf{A}_1 \mathbf{H}_3 + \mathbf{A}_2 \bar{\mathbf{U}}_2 - \mathcal{V}_0)] \\ &= \Delta \mathbf{U}^T [\mathbf{B}^T \mathbf{K}_{11} \mathbf{B}]\mathbf{U} - \mathbf{B}^T \mathbf{H}_4\end{aligned}\quad (g)$$

Requiring  $\Pi_p$  to be stationary for arbitrary  $\Delta \mathbf{U}$  results in (17-126). Note that we could have used the reduced form for  $V$ , i.e., equation (d). Also, we still have to determine the constraint forces.

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# 18 Analysis of Geometrically Nonlinear Systems

## 18-1. INTRODUCTION

In this chapter, we extend the displacement formulation to include geometric nonlinearity. The derivation is restricted to *small rotation*, i.e., where squares of rotations are negligible with respect to unity. We also consider the material to be linearly elastic and the member to be *prismatic*.

The first phase involves developing appropriate member force-displacement relations by integrating the governing equations derived in Sec. 13-9. We treat first planar deformation, since the equations for this case are easily integrated and it reveals the essential *nonlinear* effects. The three-dimensional problem is more formidable and one has to introduce numerous approximations in order to generate an explicit solution. We will briefly sketch out the solution strategy and then present a *linearized* solution applicable for doubly symmetric cross-sections.

The direct stiffness method is employed to assemble the system equations. This phase is essentially the same as for the linear case. However, the governing equations are now nonlinear.

Next, we described two iterative procedures for solving a set of nonlinear algebraic equations, successive substitution and Newton-Raphson iteration. These methods are applied to the system equations and the appropriate recurrence relations are developed. Finally, we utilize the *classical* stability criterion to investigate the stability of an equilibrium position.

## 18-2. MEMBER EQUATIONS—PLANAR DEFORMATION

Figure 18-1 shows the initial and deformed positions of the member. The centroidal axis initially coincides with the  $X_1$  direction and  $X_2$  is an axis of symmetry for the cross section. We work with displacements ( $u_1, u_2, \omega_3$ ),



Enforcing the boundary conditions on  $u_2, \omega$  at  $x = 0, L$  leads to four linear equations relating  $(C_2 \cdots C_5)$ . When the coefficient matrix is singular, the member is said to have *buckled*. In what follows, we exclude member buckling. We also neglect transverse shear deformation since its effect is small for a homogeneous cross section.

We consider the case where the end displacements are prescribed. The *net* displacements are

$$\begin{aligned} u_{\text{net}} &= u' = (\bar{u} - u_{2b})_{x=0, L} \\ \omega_{\text{net}} &= \omega' = (\bar{\omega} - u_{2b, x})_{x=0, L} \end{aligned} \quad (18-6)$$

Evaluating (18-4) with  $A_2 = \infty$ , we obtain

$$\begin{aligned} C_2 &= \omega'_A - \mu C_5 \\ C_3 &= u'_A - C_4 \\ C_4 &= -C_5 \frac{1 - \cos \mu L}{\sin \mu L} - \frac{\omega'_B - \omega'_A}{\mu \sin \mu L} \\ C_5 &= \frac{1}{D} \left\{ (u'_B - u'_A - \omega'_A L) \sin \mu L - \frac{1 - \cos \mu L}{\mu} (\omega'_B - \omega'_A) \right\} \\ D &= 2(1 - \cos \mu L) - \mu L \sin \mu L \end{aligned} \quad (18-7)$$

Note that  $D \rightarrow 0$  as  $\mu L \rightarrow 2\pi$ . This defines the upper limit on  $P$ , i.e., the member buckling load:

$$-P|_{\text{max}} = \frac{4\pi^2 EI}{L^2} \quad (18-8)$$

The end forces can be obtained with (c-e). We omit the algebraic details since they are obvious and list the final form below.

$$\begin{aligned} \bar{M}_{A3} &= M_{A3}^i + \frac{EI_3}{L} \left[ \phi_1 \omega_{A3} + \phi_2 \omega_{B3} - \frac{\phi_3}{L} (u_{B2} - u_{A2}) \right] \\ \bar{M}_{B3} &= M_{B3}^i + \frac{EI_3}{L} \left[ \phi_2 \omega_{A3} + \phi_1 \omega_{B3} - \frac{\phi_3}{L} (u_{B2} - u_{A2}) \right] \\ \bar{F}_{A2} &= F_{A2}^i + \frac{\phi_3 EI_3}{L^2} \left[ \omega_{B3} + \omega_{A3} - \frac{2}{L} (u_{B2} - u_{A2}) \right] - \frac{P}{L} (u_{B2} - u_{A2}) \\ \bar{F}_{B2} &= F_{B2}^i - \frac{\phi_3 EI_3}{L^2} \left[ \omega_{B3} + \omega_{A3} - \frac{2}{L} (u_{B2} - u_{A2}) \right] + \frac{P}{L} (u_{B2} - u_{A2}) \end{aligned} \quad (18-9)$$

$$P = \bar{F}_{B1} \quad \bar{F}_{A1} = -P$$

$$u_{B1} - u_{A1} = \frac{PL}{AE} - \int_0^L \frac{1}{2} (u_{2, x})^2 dx = \frac{PL}{AE} - e_r L$$

where

$$\begin{aligned} D &= 2(1 - \cos \mu L) - \mu L \sin \mu L \\ D\phi_1 &= \mu L (\sin \mu L - \mu L \cos \mu L) \\ D\phi_2 &= \mu L (\mu L - \sin \mu L) \\ D\phi_3 &= D(\phi_1 + \phi_2) = (\mu L)^2 (1 - \cos \mu L) \end{aligned}$$

The  $\phi_i$  functions were introduced by Livesley (Ref. 7), and are plotted in Fig. 18-2. They degenerate rapidly as  $\mu L \rightarrow 2\pi$ . The initial end forces depend on the transverse loading,  $b_2$ . If  $b_2$  is constant,

$$\begin{aligned} \bar{F}_{A2} &= \bar{F}_{B2} = -\frac{bL}{2} \\ \bar{M}_{B3} &= \frac{bL^2}{(\mu L)^2} (1 - \frac{1}{2}(\phi_1 - \phi_2)) \\ M_{A3}^i &= -\bar{M}_{B3} \end{aligned} \quad (18-10)$$

In order to evaluate the stiffness coefficients,  $P$  has to be known. If one end, say  $B$ , is *unrestrained* with respect to axial displacement, there is no difficulty since  $\bar{F}_{B1}$  is now prescribed. The relative displacement is determined from

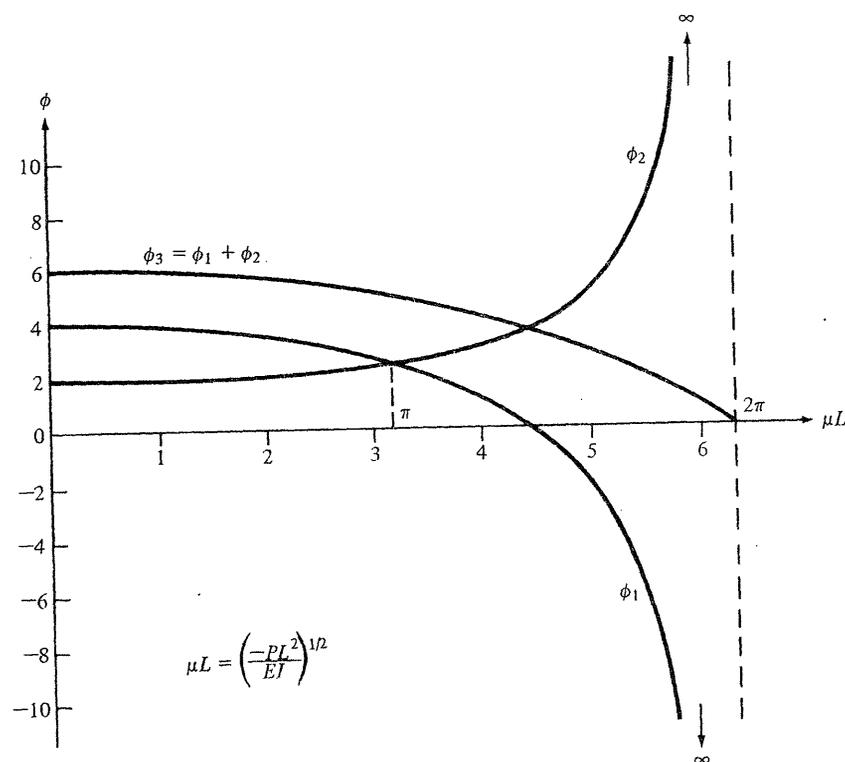
$$\begin{aligned} P &= \bar{F}_{B1} \\ u_{B1} &= u_{A1} + \frac{PL}{AE} - Le_r \\ e_r &= \frac{1}{2L} \int_0^L (u_{2, x})^2 dx = e_r(\mu L, u_{A2}, u_{B2}, \omega_A, \omega_B) \\ 2e_r &= \phi_5 (C_5')^2 + \left[ 4 \left( \frac{u_{B2} - u_{A2}}{L} \right) + \phi_6 (\omega_{B3} - \omega_{A3}) \right] C_5' \\ &\quad + \phi_7 (\omega_{B3} - \omega_{A3})^2 + \left( \frac{u_{B2} - u_{A2}}{L} \right)^2 \\ D\phi_4 &= \mu L \sin \mu L \\ C_5' &= -\frac{\phi_3}{(\mu L)^2} (\omega_{B3} - \omega_{A3}) + \phi_4 \left( \frac{u_{B2} - u_{A2}}{L} - \omega_{A3} \right) \\ \phi_7 &= \frac{1}{(\mu L \sin \mu L)^2} \left\{ \mu L (\mu L - \sin \mu L \cos \mu L) + 2(1 - \cos \mu L)^2 \right\} \\ \phi_6 &= (1 - \cos \mu L) \left\{ \phi_7 - \frac{2}{(\mu L)^2} \right\} \\ \phi_5 &= \left( \frac{1 - \cos \mu L}{2} \right) \left\{ \phi_6 + \frac{4}{(\mu L)^2} \right\} + \frac{1}{2} \left\{ 9 - \frac{\sin \mu L \cos \mu L}{\mu L} \right\} \end{aligned} \quad (18-11)$$

We call  $e_r$  the relative end shortening due to *rotation*. However, when both axial displacements are prescribed, we have to resort to iteration in order to evaluate  $P$  since  $e_r$  is a nonlinear function of  $P$ . The simplest iterative scheme is

$$P^{(i+1)} = \frac{AE}{L} (u_{B1} - u_{A1}) + AE e_r^{(i)} \quad (18-12)$$

and convergence is rapid when  $\mu L$  is not close to  $2\pi$ .

Expressions for the incremental end forces due to increments in the end displacements are needed in the Newton-Raphson procedure and also for stability analysis. If  $\mu L$  is not close to  $2\pi$ , we can assume the stability functions

Fig. 18-2. Plot of the  $\phi$  functions.

are constant and equal to their values at the initial position, when operating on (18-9). The resulting expressions are

$$\begin{aligned} d\bar{M}_{A3} &= dM_{A3}^i + \frac{EI_3}{L} \left[ \phi_1 \Delta\omega_{A3} + \phi_2 \Delta\omega_{B3} - \frac{\phi_3}{L} (\Delta u_{B2} - \Delta u_{A2}) \right] \\ d\bar{M}_{B3} &= dM_{B3}^i + \frac{EI_3}{L} \left[ \phi_2 \Delta\omega_{A3} + \phi_1 \Delta\omega_{B3} - \frac{\phi_3}{L} (\Delta u_{B2} - \Delta u_{A2}) \right] \\ d\bar{F}_{A2} &= dF_{A2}^i + \frac{\phi_3 EI_3}{L^2} \left[ \Delta\omega_{B3} + \Delta\omega_{A3} - \frac{2}{L} (\Delta u_{B2} - \Delta u_{A2}) \right] \\ &\quad - \frac{P}{L} (\Delta u_{B2} - \Delta u_{A2}) - \frac{u_{B2} - u_{A2}}{L} dP \\ d\bar{F}_{B2} &= dF_{B2}^i - (d\bar{F}_{A2} - dF_{A2}^i) \\ d\bar{F}_{B1} &= dP \quad d\bar{F}_{A1} = -dP \\ dP &= \frac{AE}{L} (\Delta u_{B1} - \Delta u_{A1}) + AE de_r \end{aligned} \quad (18-13)$$

where the incremental initial end forces are due to loading,  $\Delta b_2$ . We can obtain an estimate for  $de_r$  by assuming  $\Delta u_{2,x}$  is constant.

$$de_r = \frac{1}{L} \int_0^L u_{2,x} \Delta u_{2,x} dx \approx \left( \frac{u_{B2} - u_{A2}}{L} \right) \left( \frac{\Delta u_{B2} - \Delta u_{A2}}{L} \right) \quad (18-14)$$

The coefficients in (18-13) are tangent stiffnesses. They are not exact since we have assumed  $\phi_i$  and  $\Delta u_{2,x}$  constant. To obtain the *exact* coefficients, we have to add

$$\begin{aligned} \frac{EI_3}{L} \left[ \omega_A \phi_1' + \omega_B \phi_2' - \frac{u_{B2} - u_{A2}}{L} \phi_3' \right] d(\mu L) \\ \phi_i' = \frac{d}{d(\mu L)} \phi_i \\ d(\mu L) = -\frac{L}{2EI_3 \mu} dP \end{aligned} \quad (18-15)$$

to  $d\bar{M}_A$  and similar terms to  $d\bar{M}_B, \dots, d\bar{F}_B$ . The derivatives of the stability functions are listed below for reference:

$$\begin{aligned} \phi_3' &= \mu L + \frac{2(\mu L)^2 \sin \mu L}{D} - \frac{\phi_1 \phi_3}{\mu L} \\ \phi_3'|_{2\pi} &= -2\pi \\ \phi_1' &= \frac{\phi_1}{\mu L} \left\{ 1 - \phi_1 + \frac{1}{2} \phi_3 \right\} + \frac{1}{2} (\phi_3' - \mu L) \\ \phi_2' &= \phi_3' - \phi_1' \end{aligned} \quad (18-16)$$

We also have to use the exact expression for  $de_r$ ,

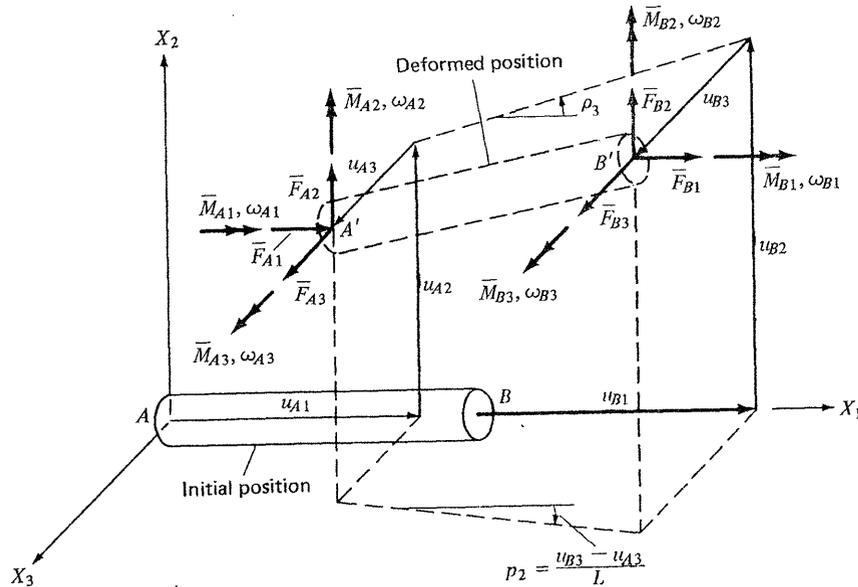
$$de_r = \frac{\partial e_r}{\partial u_{A2}} \Delta u_{A2} + \frac{\partial e_r}{\partial u_{B2}} \Delta u_{B2} + \frac{\partial e_r}{\partial \omega_A} \Delta \omega_A + \frac{\partial e_r}{\partial \omega_B} \Delta \omega_B + \frac{\partial e_r}{\partial (\mu L)} \Delta (\mu L) \quad (18-17)$$

in the equation for  $dP$ . An improvement on (18-14) is obtained by operating on (18-11), and assuming  $\mu L$  is constant.

### 18-3. MEMBER EQUATIONS—ARBITRARY DEFORMATION

The positive sense of the end forces for the three-dimensional case is shown in Fig. 18-3. Note that the force and displacement measures are referred to the fixed member frame. The governing equations for *small* rotations were derived in Sec. 13-9. They are nonlinear, and one must resort to an approximate method such as the Galerkin scheme,<sup>†</sup> in which the displacement measures are expressed in terms of prescribed functions (of  $x$ ) and parameters. The problem is transformed into a set of nonlinear algebraic equations relating the parameters. Some applications of this technique are presented in Ref. 5.

<sup>†</sup> This method is outlined in Sec. 10-6.



Note: The centroidal axis coincides with  $X_1$ .  $X_2$  and  $X_3$  are principal inertia directions.

Fig. 18-3. Notation for three-dimensional behavior.

If we consider  $b_1 = 0$ , the axial force  $F_1$  is constant along the member and the nonlinear terms involve  $\omega_1$  and coupling terms such as  $F_2 u_{s3,1}$ ;  $\omega_1 M_2$ ; etc. Neglecting these terms results in *linearized* equations, called the *Kappus equations*. Their form is:

#### Equilibrium Equations

$$\begin{aligned}
 F_1 &= P \\
 \frac{d}{dx_1} [P(u_{s2,1} + \bar{x}_3 \omega_{1,1}) + F_2] + b_2 &= 0 \\
 \frac{d}{dx_1} [P(u_{s3,1} - \bar{x}_2 \omega_{1,1}) + F_3] + b_3 &= 0 \\
 M_{T,1}^u + M_{T,1}^r + m_T + \frac{d}{dx_1} [P(\bar{x}_3 u_{s2,1} - \bar{x}_2 u_{s3,1} + \bar{\beta}_1 \omega_{1,1})] &= 0 \\
 M_{2,1} - F_3 + m_2 &= 0 \\
 M_{3,1} + F_2 + m_3 &= 0 \\
 M_{\phi,1} - M_T^r + m_\phi &= 0 \\
 \bar{\beta}_1 &= \frac{I_1}{A} + \bar{x}_2^2 + \bar{x}_3^2
 \end{aligned} \tag{18-18}$$

#### Force-Displacement Relations

$$\frac{P}{AE} = u_{1,1} + \frac{1}{2}(u_{s2,1}^2 + u_{s3,1}^2 + \bar{\beta}_1 \omega_{1,1}^2) + \omega_{1,1}(\bar{x}_3 u_{s2,1} - \bar{x}_2 u_{s3,1})$$

$$u_{s2,1} - \omega_3 = \frac{1}{G} \left( \frac{F_2}{A_2} + \frac{F_3}{A_{23}} + \frac{x_{3r}}{J} M_T^r \right)$$

$$u_{s3,1} + \omega_2 = \frac{1}{G} \left( \frac{F_2}{A_{23}} + \frac{F_3}{A_3} + \frac{x_{2r}}{J} M_T^r \right)$$

$$\omega_{1,1} = \frac{M_T^u}{GJ} \quad f_{,1} = \frac{M_\phi}{E_r I_\phi}$$

$$\omega_{2,1} = \frac{M_2}{EI_2} \quad \omega_{3,1} = \frac{M_3}{EI_3}$$

$$f + \omega_{1,1} = \frac{1}{GJ} (C_r M_T^r + x_{3r} F_2 + x_{2r} F_3)$$

Boundary Conditions (+ for  $x = L$ , - for  $x = 0$ )

$$\begin{aligned}
 P &= \pm \bar{F}_1 \\
 P(u_{s2,1} + \bar{x}_3 \omega_{1,1}) + F_2 &= \pm \bar{F}_2 \\
 P(u_{s3,1} - \bar{x}_2 \omega_{1,1}) + F_3 &= \pm \bar{F}_3 \\
 M_T^u + M_T^r + P(\bar{x}_3 u_{s2,1} - \bar{x}_2 u_{s3,1} + \bar{\beta}_1 \omega_{1,1}) &= \pm \bar{M}_T \\
 M_2 &= \pm \bar{M}_2 \quad M_3 = \pm \bar{M}_3 \quad M_\phi = \pm \bar{M}_\phi
 \end{aligned}$$

To interpret the *linearization*, we consider (13-81). If one neglects the nonlinear terms in the shearing strains,

$$\begin{aligned}
 \gamma_{12} &\approx \hat{u}_{1,2} + \hat{u}_{2,1} \\
 \gamma_{13} &\approx \hat{u}_{1,3} + \hat{u}_{3,1}
 \end{aligned} \tag{a}$$

takes the extensional strain as

$$\epsilon_1 \approx \hat{u}_{1,1} + \frac{1}{2}(\hat{u}_{2,1}^2 + \hat{u}_{3,1}^2)|_{x_2=x_3=0} + (x_2^2 + x_3^2)\omega_{1,1}^2 \tag{b}$$

and assumes

$$\begin{aligned}
 \iint x_2(x_2^2 + x_3^2) dA &= 0 \\
 \iint x_3(x_2^2 + x_3^2) dA &= 0 \\
 \iint \phi(x_2^2 + x_3^2) dA &= 0
 \end{aligned} \tag{c}$$

one obtains (13-81). Equations (c) are exact when the section is doubly symmetric. Assumptions (a) and (b) are reasonable if  $\omega_{1,1}$  is small w.r. to  $u_{2,1}$  and  $u_{3,1}$ . However, they introduce considerable error when  $\omega_{1,1}$  is the dominant term. This has been demonstrated by Black (Ref. 5).

When the cross section is doubly symmetric,

$$\begin{aligned}
 \bar{x}_2 = \bar{x}_3 = x_{2r} = x_{3r} &= \frac{1}{A_{23}} = 0 \\
 \bar{\beta}_1 &= \frac{I_1}{A} = r^2
 \end{aligned} \tag{18-19}$$

( $r$  is the radius of gyration with respect to the centroid) and the problem uncouples to—

1. Flexure in  $X_1$ - $X_2$  plane
2. Flexure in  $X_1$ - $X_3$  plane
3. Restrained torsion

We have already determined the solution for flexure in the  $X_1$ - $X_2$  plane. If we introduce a subscript for  $\mu$  and  $\phi_j$ ,

$$(\mu_2)^2 = \frac{-P}{EI_3} \quad (\mu_3)^2 = \frac{-P}{EI_2} \quad (18-20)$$

$$\phi_{21} = \phi_1(\mu_2 L) \quad \phi_{31} = \phi_1(\mu_3 L)$$

and then replace

$$\begin{aligned} u_2 &\rightarrow u_3 & \omega_2 &\rightarrow \omega_3 \\ u_3 &\rightarrow -u_2 & \omega_3 &\rightarrow -\omega_2 \\ F_2 &\rightarrow F_3 & M_2 &\rightarrow M_3 \\ F_3 &\rightarrow -F_2 & M_3 &\rightarrow -M_2 \end{aligned} \quad (18-21)$$

in (18-9), (18-13), we obtain the member relations for flexure in the  $X_1$ - $X_3$  frame. For example,

$$\bar{M}_{A3} = M_{A3}^i + \frac{EI_3}{L} \left[ \phi_{21}\omega_{A3} + \phi_{22}\omega_{B3} - \frac{\phi_{23}}{L}(u_{B2} - u_{A2}) \right] \quad (18-22)$$

$$\bar{M}_{A2} = M_{A2}^i + \frac{EI_2}{L} \left[ \phi_{31}\omega_{A2} + \phi_{32}\omega_{B2} + \frac{\phi_{33}}{L}(u_{B3} - u_{A3}) \right]$$

and

$$\bar{F}_{A2} = \dots$$

$$\bar{F}_{A3} = F_{A3}^i + \frac{\phi_{33}EI_2}{L^2} \left[ -\omega_{B2} - \omega_{A2} - \frac{2}{L}(u_{B3} - u_{A3}) \right] - \frac{P}{L}(u_{B3} - u_{A3})$$

The expressions for the axial end forces expands to

$$\begin{aligned} F_{B1} &= P & F_{A1} &= -P \\ P &= \frac{AE}{L}(u_{B1} - u_{A1}) + AE(e_{r1} + e_{r2} + e_{r3}) \\ e_{r1} &= \frac{r^2}{2L} \int_0^L \omega_{1,1}^2 dx_1 & e_{r2} &= \frac{1}{2L} \int_0^L (u_{2,x})^2 dx_1 \\ e_{r3} &= \frac{1}{2L} \int_0^L (u_{3,x})^2 dx_1 \end{aligned} \quad (18-23)$$

where  $e_{r3}$  is obtained from  $e_{r2}$  by applying (18-21).

We generate the restrained torsion solution following the procedure described in Example 13-7. If the joints are moment resisting (i.e., rigid), it is reasonable to assume no warping, which requires  $f = 0$  at  $x = 0, L$ . The corresponding solution is summarized below:

$$\bar{P} = \frac{r^2 P}{GJ} \quad u^2 = \frac{GJ}{E_r I_\phi} \frac{1 + \bar{P}}{1 + C_r(1 + \bar{P})}$$

$$\bar{M}_{B1} = \frac{GJ}{L} \phi_t (\omega_{B1} - \omega_{A1})$$

$$\bar{M}_{A1} = -\bar{M}_{B1}$$

$$\phi_t = \frac{1 + \bar{P}}{1 + \frac{1 - \cosh \mu L}{\sinh \mu L} \left[ \frac{2}{\mu L(1 + C_r(1 + \bar{P}))} \right]} \quad (18-24)$$

$$\omega_1 = \omega_{A1} + \frac{\bar{M}_{B1}}{GJ(1 + P)} \left\{ x + \frac{1}{\mu(1 + C_r(1 + \bar{P}))} \left[ -\sinh \mu x + \frac{1 - \cosh \mu L}{\sinh \mu L} (1 - \cosh \mu x) \right] \right\}$$

We neglect shear deformation due to restrained torsion by setting  $C_r = 0$ . If warping restraint is neglected,

$$E_r I_\phi = 0 \Rightarrow \mu^2 = \infty \quad \phi_t \Rightarrow 1 + \bar{P} \quad (18-25)$$

At this point, we summarize the member force-displacement relations for a doubly symmetric cross section. For convenience, we introduce matrix notation:

$$\mathcal{F}_B = \{\bar{F}_1 \bar{F}_2 \bar{F}_3 \bar{M}_1 \bar{M}_2 \bar{M}_3\}_B$$

$$\mathcal{U}_B = \{u_1 u_2 u_3 \omega_1 \omega_2 \omega_3\}_B$$

etc.

$$\mathcal{F}_B = \mathcal{F}_B^i + \mathbf{k}_{BB} \mathcal{U}_B + \mathbf{k}_{BA} \mathcal{U}_A + \mathcal{F}_r$$

$$\mathcal{F}_A = \mathcal{F}_A^i + (\mathbf{k}_{BA})^T \mathcal{U}_B + \mathbf{k}_{AA} \mathcal{U}_A - \mathcal{F}_r$$

where  $\mathcal{F}_r$  contains nonlinear terms due to chord rotation and end shortening  $= \left\{ AE(e_{r1} + e_{r2} + e_{r3}); \frac{P}{L}(u_{B2} - u_{A2}); \frac{P}{L}(u_{B3} - u_{A3}); 0; 0; 0 \right\}$ ;  $\mathcal{F}^i$  contains the initial end forces due to member loads; and

	$\frac{AE}{L}$				
		$2\phi_{23} \frac{EI_3}{L^3}$			$-\phi_{23} \frac{EI_3}{L^2}$
			$2\phi_{33} \frac{EI_2}{L^3}$	$\phi_{33} \frac{EI_2}{L^2}$	
$\mathbf{k}_{BB} =$			$\phi_t \frac{GJ}{L}$		
Sym				$\phi_{31} \frac{EI_2}{L}$	
					$\phi_{21} \frac{EI_3}{L}$

$$\mathbf{k}_{BA} = \begin{array}{|c|c|c|c|c|} \hline \frac{AE}{L} & & & & \\ \hline & -2\phi_{23} \frac{EI_3}{L^3} & & & -\phi_{23} \frac{EI_3}{L^2} \\ \hline & & -2\phi_{33} \frac{EI_2}{L^3} & & \phi_{33} \frac{EI_2}{L^2} \\ \hline & & & -\phi_t \frac{GJ}{L} & \\ \hline & & -\phi_{33} \frac{EI_2}{L^2} & & \phi_{32} \frac{EI_2}{L} \\ \hline & \phi_{23} \frac{EI_3}{L^2} & & & \phi_{22} \frac{EI_3}{L} \\ \hline \end{array}$$

$$\mathbf{k}_{AA} = \begin{array}{|c|c|c|c|c|} \hline \frac{AE}{L} & & & & \\ \hline & 2\phi_{23} \frac{EI_3}{L^3} & & & \phi_{23} \frac{EI_3}{L^2} \\ \hline & & 2\phi_{33} \frac{EI_2}{L^3} & & -\phi_{33} \frac{EI_2}{L^2} \\ \hline & & & \phi_t \frac{GJ}{L} & \\ \hline Sym & & & & \phi_{31} \frac{EI_2}{L} \\ \hline & & & & \phi_{21} \frac{EI_3}{L} \\ \hline \end{array}$$

Operating on  $\mathcal{F}_B, \mathcal{F}_A$  leads to the incremental equations, i.e., the three-dimensional form of (18-13). Assuming the stability functions are constant and taking

$$d\phi_t \approx d\bar{P} = \frac{r^2}{GJ} dP$$

$$de_r \approx \frac{1}{L^2} \left\{ (u_{B2} - u_{A2})(\Delta u_{B2} - \Delta u_{A2}) + (u_{B3} - u_{A3})(\Delta u_{B3} - \Delta u_{A3}) + r^2(\omega_{B1} - \omega_{A1})(\Delta \omega_{B1} - \Delta \omega_{A1}) \right\} \quad (18-27)$$

we obtain

$$\begin{aligned} d\bar{\mathcal{F}}_B &= d\mathcal{F}_B^i + (\mathbf{k}_{BB} + \mathbf{k}_r)\Delta \mathcal{U}_B + (\mathbf{k}_{BA} - \mathbf{k}_r)\Delta \mathcal{U}_A \\ d\bar{\mathcal{F}}_A &= d\mathcal{F}_A^i + (\mathbf{k}_{BA} - \mathbf{k}_r)^T \Delta \mathcal{U}_B + (\mathbf{k}_{AA} + \mathbf{k}_r)\Delta \mathcal{U}_A \end{aligned} \quad (18-28)$$

where  $\mathbf{k}_r$  is the incremental stiffness matrix due to rotation,

$$\mathbf{k}_r = \frac{AE}{L} \begin{array}{|c|c|c|c|c|c|} \hline 0 & \rho_3 & -\rho_2 & r^2\rho_1 & 0 & 0 \\ \hline & \rho_3^2 + \frac{L\bar{F}_{B1}}{AE} & -\rho_2\rho_3 & r^2\rho_1\rho_3 & 0 & 0 \\ \hline & & \rho_2^2 + \frac{L\bar{F}_{B1}}{AE} & -r^2\rho_1\rho_2 & 0 & 0 \\ \hline & Symmetrical & & (r^2\rho_1)^2 & 0 & 0 \\ \hline & & & & 0 & 0 \\ \hline & & & & & 0 \\ \hline \end{array}$$

$$\rho_3 = \frac{1}{L}(u_{B2} - u_{A2}) \quad \rho_2 = \frac{-1}{L}(u_{B3} - u_{A3}) \quad \rho_1 = \frac{1}{L}(\omega_{B1} - \omega_{A1})$$

If  $P$  is close to the member buckling load, one must include additional terms due to the variation in the stability functions and use the exact expression for  $de_r$ .

Kappas's equations have also been solved explicitly for a monosymmetric section with warping and shear deformation neglected. Since the equations are linear, one can write down the general solution for an arbitrary cross section. It will involve twelve integration constants which are evaluated by enforcing the displacement boundary conditions. The algebra is untractable unless one introduces symmetry restrictions.

#### 18-4. SOLUTION TECHNIQUES; STABILITY ANALYSIS

In this section, we present the mathematical background for two solution techniques, successive substitution and Newton-Raphson iteration, and then apply them to the governing equations for a nonlinear member system.

Consider the problem of solving the nonlinear equation

$$\psi(x) = 0 \quad (18-29)$$

Let  $\bar{x}$  represent one of the roots. By definition,

$$\psi(\bar{x}) \equiv \bar{\psi} = 0 \quad (18-30)$$

In the method of successive substitution,† (18-29) is rewritten in an equivalent form,

$$x = g(x) \quad (18-31)$$

and successive estimates of the solution are determined, using

$$x^{(k+1)} = g(x^{(k)}) \equiv g^{(k)} \quad (18-32)$$

where  $x^{(k)}$  represents the  $k$ th estimate.

The exact solution satisfies

$$\bar{x} = \bar{g} \quad (a)$$

† See Ref. 9.

Then,

$$\bar{x} - x^{(k+1)} = \bar{g} - g^{(k)} \tag{b}$$

Expanding  $\bar{g}$  in a Taylor series about  $x^{(k)}$ ,

$$\bar{g} = g^{(k)} + g'_{,x}(x^{(k)})(\bar{x} - x^{(k)}) + \frac{1}{2}g''_{,xx}(x^{(k)})(\bar{x} - x^{(k)})^2 + \dots \tag{c}$$

and retaining only the first two terms lead to the convergence measure

$$\bar{x} - x^{(k+1)} = (\bar{x} - x^{(k)})|g'_{,x}|_{x=\xi_k} \tag{18-33}$$

where  $\xi_k$  is between  $x^{(k)}$  and  $\bar{x}$ .

In the Newton-Raphson method,†  $\psi(\bar{x})$  is expanded in a Taylor series about  $x^{(k)}$ ,

$$\psi(\bar{x}) = \psi^{(k)} + \psi'_{,x}(x^{(k)})\Delta x + \frac{1}{2}\psi''_{,xx}(x^{(k)})(\Delta x)^2 + \dots = 0 \tag{a}$$

where  $\Delta x$  is the exact correction to  $x^{(k)}$ ,

$$\Delta x = \bar{x} - x^{(k)} \tag{b}$$

An estimate for  $\Delta x$  is obtained by neglecting second- and higher-order terms:

$$\begin{aligned} \Delta x^{(k)} &= -\frac{\psi^{(k)}}{\psi'_{,x}(x^{(k)})} \\ x^{(k+1)} &= x^{(k)} + \Delta x^{(k)} \end{aligned} \tag{18-34}$$

The convergence measure for this method can be obtained by combining (a) and (18-34), and has the form

$$(\bar{x} - x^{(k+1)})\psi'_{,x}(x^{(k)}) = -\frac{1}{2}(\bar{x} - x^{(k)})^2|\psi''_{,xx}|_{x=\xi_k} \tag{18-35}$$

Note that the Newton-Raphson method has *second-order* convergence whereas successive substitution has only *first-order* convergence.

We consider next a set of  $n$  nonlinear equations:

$$\begin{aligned} \Psi &= \{\psi_1 \ \psi_2 \ \dots \ \psi_n\} = 0 \\ \psi_i &= \psi(x_1, x_2, \dots, x_n) \end{aligned} \tag{18-36}$$

An exact solution is denoted by  $\bar{x}$ . Also,  $\psi(\bar{x}) = \bar{\Psi}$ .

In successive substitution, (18-36) is rearranged to

$$\mathbf{ax} = \mathbf{c} - \mathbf{g} \tag{18-37}$$

where  $\mathbf{a}$ ,  $\mathbf{c}$  are constant,  $\mathbf{g} = \mathbf{g}(\mathbf{x})$ , and the recurrence relation is taken as

$$\mathbf{ax}^{(k+1)} = \mathbf{c} - \mathbf{g}^{(k)} \tag{18-38}$$

The exact solution satisfies

$$\mathbf{a}\bar{\mathbf{x}} = \mathbf{c} - \bar{\mathbf{g}} \tag{a}$$

Then,

$$\mathbf{a}(\bar{\mathbf{x}} - \mathbf{x}^{(k+1)}) = -(\bar{\mathbf{g}} - \mathbf{g}^{(k)}) \tag{b}$$

† See Ref. 9.

Expanding  $\bar{\mathbf{g}}$  in a Taylor series about  $\mathbf{x}^{(k)}$ ,

$$\bar{\mathbf{g}} = \mathbf{g}^{(k)} + \mathbf{g}'_{,x}(x^{(k)})(\bar{\mathbf{x}} - \mathbf{x}^{(k)}) + \dots \tag{c}$$

$$\mathbf{g}'_{,x} = \left[ \frac{\partial g_j}{\partial x_r} \right] = \begin{bmatrix} g_{1,1} & g_{1,2} & \dots & g_{1,n} \\ g_{2,1} & g_{2,2} & \dots & g_{2,n} \\ \vdots & \vdots & \ddots & \vdots \\ g_{n,1} & g_{n,2} & \dots & g_{n,n} \end{bmatrix} \tag{d}$$

and retaining only the first two terms results in the convergence measure

$$(\mathbf{x} - \mathbf{x}^{(k+1)}) = \mathbf{a}^{-1}|\mathbf{g}'_{,x}|_{x=\xi_k}(\mathbf{x} - \mathbf{x}^{(k)}) \tag{18-39}$$

where  $\xi_k$  lies between  $\mathbf{x}^k$  and  $\bar{\mathbf{x}}$ . For convergence, the norm of  $\mathbf{a}^{-1}|\mathbf{g}'_{,x}|$  must be less than unity.

The generalized Newton-Raphson method consists in first expanding  $\Psi(\bar{\mathbf{x}})$  about  $\mathbf{x}^{(k)}$ ,

$$\Psi(\bar{\mathbf{x}}) = \Psi^{(k)} + d\Psi^{(k)} + \frac{1}{2}d^2\Psi|_{\xi_k} = 0$$

where

$$\begin{aligned} d\Psi^{(k)} &= \Psi'_{,x}(x^{(k)})\Delta \mathbf{x} = \left[ \frac{\partial \psi_j}{\partial x_r} \right] \{\bar{x}_r - x_r^{(k)}\} \\ d^2\Psi &= \{d^2\psi_j\} \\ d^2\psi_j &= (\Delta \mathbf{x})^T \left[ \frac{\partial^2 \psi_j}{\partial x_r \partial x_s} \right] (\Delta \mathbf{x}) \end{aligned} \tag{18-40}$$

Neglecting the second differential leads to the recurrence relation

$$\begin{aligned} d\Psi^{(k)} &= \Psi'_{,x}(x^{(k)})\Delta \mathbf{x}^{(k)} = -\Psi^{(k)} \\ \mathbf{x}^{(k+1)} &= \mathbf{x}^{(k)} + \Delta \mathbf{x}^{(k)} \end{aligned} \tag{18-41}$$

The corresponding convergence measure is

$$\Psi'_{,x}(x^{(k)})(\bar{\mathbf{x}} - \mathbf{x}^{(k+1)}) = -\frac{1}{2}d^2\Psi|_{\xi_k} \tag{18-42}$$

Let us now apply these solution techniques to the structural problem. The governing equations are the nodal force-equilibrium equations referred to the *global* system frame,

$$\Psi = \mathcal{P}_e - \mathcal{P}_m = 0 \tag{18-43}$$

where  $\mathcal{P}_e$  contains the external nodal forces and  $-\mathcal{P}_m$  is the summation of the member end forces incident on node  $i$ . One first has to rotate the member end forces, (18-26), from the member frame to the global frame using

$$\begin{aligned} \mathcal{F}^o &= (\mathcal{R}^{on})^T \mathcal{F}^n \\ \mathbf{k}^o &= (\mathcal{R}^{on})^T \mathbf{k}^n \mathcal{R}^{on} \end{aligned} \tag{a}$$

In our formulation, the member frame is *fixed*, i.e.  $\mathcal{R}^{on}$  is constant. We introduce the displacement restraints and write the final equations as

$$\begin{aligned} \Psi &= \mathbf{P}_e - \mathbf{P}_m = 0 \\ \mathbf{P}_m &= \mathbf{P}_i + \mathbf{P}_r + \mathbf{KU} \end{aligned} \tag{18-44}$$

Note that  $\mathbf{K}$  and  $\mathbf{P}_i$  depend on the axial forces while  $\mathbf{P}_r$  depends on both the axial force and the member rigid body chord rotation. If the axial forces are small in comparison to the member buckling loads, we can replace  $\mathbf{K}$  with  $\mathbf{K}_l$ , the linear stiffness matrix.

Applying successive substitution, we write

$$\mathbf{K}\mathbf{U} = \mathbf{P}_e - \mathbf{P}_i - \mathbf{P}_r \quad (\text{a})$$

and iterate on  $\mathbf{U}$ , holding  $\mathbf{K}$  constant during the iteration:

$$\mathbf{K}\mathbf{U}^{(n)} = \mathbf{P}_e - \mathbf{P}_i - \mathbf{P}_r^{(n-1)} \quad (18-45)$$

We employ (18-45) together with an incremental loading scheme since  $\mathbf{K}$  is actually a variable. The steps are outlined here:

1. Apply the first load increment,  $\mathbf{P}_{e(1)}$ , and solve for  $\mathbf{U}_{(1)}$ , using  $\mathbf{K} = \mathbf{K}_l$ .
2. Update  $\mathbf{K}$  using the axial forces corresponding to  $\mathbf{P}_{e(1)}$ . Then apply  $\mathbf{P}_{e(2)}$  and iterate on

$$\mathbf{K}_{(1)}\mathbf{U}^{(n)} = \mathbf{P}_{e(1)} + \mathbf{P}_{e(2)} - \mathbf{P}_r^{(n-1)}$$

3. Continue for successive load increments.

A convenient convergence criterion is the relative change in the Euclidean norm,  $N$ , of the nodal displacements.

$$N = (\mathbf{U}^T\mathbf{U})^{1/2} \quad (18-46)$$

$$\left( \frac{N^{(n+1)}}{N^{(n)}} - 1 \right)_{\text{abs. valuc}} \leq \varepsilon \quad (\text{a specified value})$$

This scheme is particularly efficient when the member axial forces are small with respect to the Euler loads since, in this case, we can take  $\mathbf{K} = \mathbf{K}_l$  during the entire solution phase.

In the Newton-Raphson procedure, we operate on  $\psi$  according to (18-41):

$$d\psi^{(n)} = -\psi^{(n)} \quad (\text{a})$$

Now,  $\mathbf{P}_e$  is prescribed so that

$$\begin{aligned} d\psi^{(n)} &= -d\mathbf{P}_m^{(n)} \quad \text{due to } \Delta\mathbf{U} \\ &= -[d\mathbf{P}_i + d\mathbf{P}_r + \mathbf{K}\Delta\mathbf{U} + (d\mathbf{K})\mathbf{U}]_{\mathbf{U}^{(n)}} \\ &= -[\mathbf{K}_t\Delta\mathbf{U}]_{\mathbf{U}^{(n)}} \end{aligned} \quad (18-47)$$

where  $\mathbf{K}_t$  denotes the tangent stiffness matrix. The iteration cycle is

$$\begin{aligned} \mathbf{K}_t^{(n)}\Delta\mathbf{U}^{(n)} &= \mathbf{P}_e - \mathbf{P}_m^{(n)} \\ \mathbf{U}^{(n+1)} &= \mathbf{U}^{(n)} + \Delta\mathbf{U}^{(n)} \end{aligned} \quad (18-48)$$

We iterate on (18-48) for successive load increments. This scheme is more expensive since  $\mathbf{K}_t$  has to be updated for each cycle. However, its convergence rate is more rapid than direct substitution. If we assume the stability functions

are constant in forming  $d\mathbf{P}_m$  due to  $\Delta\mathbf{U}$ , the tangent stiffness matrix reduces to

$$\begin{aligned} d\mathbf{K} &\approx \mathbf{0} & d\mathbf{P}_i &\approx \mathbf{0} \\ \mathbf{K}_t &\approx \mathbf{K} + \mathbf{K}_r \end{aligned} \quad (18-49)$$

where  $\mathbf{K}_r$  is generated with (18-28). We include the incremental member loads in  $\mathbf{P}_e$  at the start of the iteration cycle. Rather than update  $\mathbf{K}_t$  at each cycle, one can hold  $\mathbf{K}_t$  fixed for a limited number of cycles. This is called *modified* Newton-Raphson. The convergence rate is lower than for regular Newton-Raphson but higher than successive substitution.

We consider next the question of stability. According to the classical stability criterion,<sup>†</sup> an equilibrium position is classified as:

$$\begin{aligned} \text{stable} & & d^2W_m - d^2W_e &> 0 \\ \text{neutral} & & d^2W_m - d^2W_e &= 0 \\ \text{unstable} & & d^2W_m - d^2W_e &< 0 \end{aligned} \quad (18-50)$$

where  $d^2W_e$  is the second-order work done by the external forces during a displacement increment  $\Delta\mathbf{U}$ , and  $d^2W_m$  is the second-order work done by the member end forces acting on the members. With our notation,

$$\begin{aligned} d^2W_e &= \left( \frac{d}{d\mathbf{U}} \mathbf{P}_e \right)^T \Delta\mathbf{U} \\ d^2W_m &= \left( \frac{d}{d\mathbf{U}} \mathbf{P}_m \right)^T \Delta\mathbf{U} \\ &= \Delta\mathbf{U}^T \mathbf{K}_t \Delta\mathbf{U} \end{aligned} \quad (18-51)$$

and the criteria transform to

$$\begin{aligned} (\Delta\mathbf{U})^T \mathbf{K}_t \Delta\mathbf{U} - \left( \frac{d}{d\mathbf{U}} \mathbf{P}_e \right)^T \Delta\mathbf{U} &< 0 & \text{stable} \\ &= 0 & \text{neutral} \\ &> 0 & \text{unstable} \end{aligned} \quad (18-52)$$

The most frequent case is  $\mathbf{P}_e$  prescribed, and for a constant loading, the tangent stiffness matrix must be *positive definite*.

To detect instability, we keep track of the sign of the determinant of the tangent stiffness matrix during the iteration. The sign is obtained at *no* cost (i.e., no additional computation) if Gauss elimination or the factor method are used to solve the *correction* equation, (18-48). When the determinant changes sign, we have passed through a stability transition. Another indication of the existence of a bifurcation point ( $\mathbf{K}_t$  singular) is the degeneration of the convergence rate for Newton-Raphson. The correction tends to diverge and oscillate in sign and one has to employ a higher iterative scheme.

Finally, we consider the special case where the loading does not produce significant chord rotation. A typical example is shown in Fig. 18-4. Both the

<sup>†</sup> See Secs. 7-6 and 10-6.

frame and loading are symmetrical and the displacement is due only to shortening of the columns. To investigate the stability of this structure, we delete† the rotation terms in  $\mathbf{K}_r$  and write

$$\mathbf{K}_t = \mathbf{K} + \lambda \mathbf{K}'_r = \mathbf{K}_t(\lambda) \quad (18-53)$$

where  $\mathbf{K}'_r$  is due to a unit value of the load parameter  $\lambda$ . The member axial forces are determined from a linear analysis. Then, the bifurcation problem reduces to determining the value of  $\lambda$  for which a nontrivial solution of

$$(\mathbf{K} + \lambda \mathbf{K}'_r) \Delta \mathbf{U} = \mathbf{0} \quad (18-54)$$

exists. This is a nonlinear eigenvalue problem, since  $\mathbf{K} = \mathbf{K}(\lambda)$ .

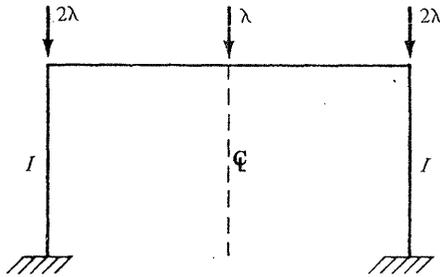


Fig. 18-4. Example of structure and loading for which linearized stability analysis is applicable.

In *linearized* stability analysis,  $\mathbf{K}$  is assumed to be  $\mathbf{K}_t$  and one solves

$$\mathbf{K}_t \Delta \mathbf{U} = -\lambda \mathbf{K}'_r \Delta \mathbf{U} \quad (18-55)$$

Both  $\mathbf{K}_t$  and  $\mathbf{K}'_r$  are symmetrical. Also,  $\mathbf{K}_t$  is positive definite. Usually, only the lowest critical load is of interest, and this can be obtained by applying inverse iteration‡ to

$$\begin{aligned} (-\mathbf{K}'_r) \Delta \mathbf{U} &= \bar{\lambda} \mathbf{K}_t \Delta \mathbf{U} \\ \bar{\lambda} &= \frac{1}{\lambda} \end{aligned} \quad (18-56)$$

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† Set  $\rho_1 = \rho_2 = \rho_3 = 0$  in (18-28).

‡ See Refs. 11 and 12 of Chapter 2.

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## Index

- Associative multiplication, 8  
Augmented branch-node incidence matrix, 124, 222  
Augmented matrix, 33  
Axial deformation, influence on bending of planar member, 472
- Bar stiffness matrix, 180  
Bifurcation; *see* Neutral equilibrium  
Bimoment,  $M\phi$ , 373  
Branch-node incidence table, 121, 145
- $C\phi$ ,  $C_r$ ,  $C_{rr}$ —coefficients appearing in complementary energy expression for restrained torsion, 387, 388, 416  
Canonical form, 58  
Cartesian formulation, principle of virtual forces for a planar member, 465  
Castigliano's principles, 176  
Cayley-Hamilton Theorem, 63  
Center of twist, 383, 389  
Characteristic values of a matrix, 46  
Chord rotation,  $\rho$ , 586  
Circular helix, definition equation, 84, 86  
Circular segment  
  out-of-plane loading, 504  
  restrained warping solution, 509  
Classical stability criterion  
  continuum, 256  
  member system, 601  
  truss, 170  
Closed ring, out-of-plane loading, 503  
Cofactor, 19  
Column matrix, 4  
Column vector, 4  
Complementary energy  
  continuum, 261  
  member system, 572  
  planar curved member, 434  
  restrained torsion, 385; 387, 388  
  unrestrained torsion-flexure, 301  
Conformable matrices, 8, 35  
Connectivity matrix, member system, 563  
Connectivity table for a truss, 121, 143  
Consistency, of a set of linear algebraic equations, 31, 44
- Constraint conditions treated with Lagrange multipliers, 76, 80  
Curved member  
  definition of *thin* and *thick*, 434  
  thin, 487  
  slightly twisted, 487
- Defect, of a system of linear algebraic equations, 31  
Deformation  
  for out-of-plane loading of a circular member, transverse shear, twist, and bending, 498  
  for planar member, stretching and transverse shear vs. bending, 454  
Deformation constraints  
  force method, 573  
  displacement method, 576  
  variational approach, 583  
Deformed geometry, vector orientation, 239  
Degree of static indeterminacy  
  member, 555, 567  
  truss, 210  
Determinant, 16, 37, 39  
Diagonal matrix, 10  
Differential notation for a function, 70, 72, 79  
Direction cosine matrix for a bar, 119  
Discriminant, 40, 59  
Distributive multiplication, 8
- Echelon matrix, 29  
Effective shear area, cross-sectional properties, 302  
Elastic behavior, 125, 248  
End shortening due to geometrically nonlinear behavior, 589  
Engineering theory of a member, basic assumptions, 330, 485  
Equivalence, of matrices, 27  
Equivalent rigid body displacements, 334, 414, 430  
Euler equations for a function, 73  
Eulerian strain, 234

- First law of thermodynamics, 248  
 Fixed end forces  
   prismatic member, 523  
   thin planar circular member, 528  
 Flexibility matrix  
   arbitrary curved member, 515  
   circular helix, 534  
   planar member, 462  
   prismatic member, 345, 521  
   thin planar circular member, 526  
 Flexural warping functions, 296, 300/ $f_n$   
 Frenet equations, 91  
  
 Gauss's integration by parts formula, 254  
 Geometric compatibility equation  
   arbitrary member, 499  
   continuum, 259, 264  
   member system, 569  
   planar member, 463, 466  
   prismatic member, 355  
   truss, 160, 212, 216, 223  
   unrestrained torsion, 279, 315  
 Geometric stiffness matrix for a bar, 200  
 Geometrically nonlinear restrained torsion solution, 595  
 Green's strain tensor, 234  
  
 Hookean material, 126, 249  
 Hyperelastic material, 248  
  
 Incremental system stiffness matrix  
   member system, 601  
   truss, 193  
 Inelastic behavior, 125  
 Initial stability  
   member system, 562  
   truss, 137  
 Invariants of a matrix, 59, 62  
 Isotropic material, 252  
  
 Kappus equations, 592  
 Kronecker delta notation, 11  
  
 Lagrange multipliers, 76, 80, 583  
 Lagrangian strain, 234  
 Lamé constants, 253  
 Laplace expansion for a determinant, 20, 38  
 Linear connected graph, 218  
 Linear geometry, 120, 143, 237  
 Linearized stability analysis, 602  
 Local member reference frame, 92  
  
 Marguerre equations, 449, 456  
 Material compliance matrix, 249  
 Material rigidity matrix, 249  
 Matrix iteration, computational method, 201  
 Maxwell's law of reciprocal deflections, 356  
 Member, definition, 271  
 Member buckling, 588  
 Member force displacement relations, 537, 546, 556  
 Member on an elastic foundation, 384, 369  
 Mesh, network, 220  
 Minor, of a square array, 19  
 Modal matrix, 52  
 Modified Neuton-Raphson iteration, 601  
 Moment,  $M_R$ , 375  
 Mushtari's equations, 444  
  
 Natural member reference frame, 92  
 Negative definite, 58  
 Negligible transverse shear deformation, planar member, 443, 454, 498  
 Network, topological, 220  
 Neutral equilibrium, 170, 256, 601  
 Newton-Raphson iteration, member system, 598  
 Normalization of a vector, 49  
 Null matrix, 4  
  
 One-dimensional deformation measures, 335, 338, 432  
   arbitrary member, 491  
 Orthogonal matrices and transformations, 50, 53  
 Orthotropic material, 250, 251  
  
 Permutation matrix, 42, 135  
 Permutation of a set of integers, 16, 37  
 Piecewise linear material, 126, 146  
 Plane curve, 98, 425  
 Poisson's ratio, 252  
 Positive definite matrix, 58, 63  
 Positive semi-definite matrix, 58  
 Postmultiplication, matrix, 8  
 Potential energy function, member system, 571  
 Premultiplication, matrix, 8  
 Primary structure  
   member system, 568  
   planar member, 463  
   prismatic member, 354  
   truss, 211  
 Principle minors, 55  
 Principle of virtual displacements  
   member system, 570  
   planar member, 442  
 Principle of virtual forces  
   arbitrary member, 490, 492, 512  
   member system, 571  
   planar member, 435, 458  
   prismatic member, 338, 351  
 Quadratic forms, 57

- Quasi-diagonal matrix, 15, 38  
 Quasi-triangular matrix, 39  
  
 Radius of gyration, 434  
 Rank of a matrix, 27, 42, 43  
 Rayleigh's quotient, 75, 79  
 Reissner's principle  
   continuum, 270  
   member, 383, 414  
   member system, 573  
 Relative minimum or maximum value of a function, relative extrema, 66  
 Restrained torsion solution, prismatic member  
   linear geometry, 391  
   nonlinear geometry, 595  
 Restrained torsion stress distribution and cross-sectional parameters  
   channel section, 401  
   multicell section, 411  
   symmetrical I section, 398  
   thin rectangular cell, 407  
 Rigid body displacement transformation, 109  
 Rotation transformation matrix, 101, 232  
 Row matrix, 4  
  
 Self-equilibrating force systems, 160, 211, 258  
   member systems, 568  
 Shallow member, assumptions, 448  
 Shear center, 297, 300, 309, 378, 389  
 Shear flow, 287  
 Shear flow distribution for unrestrained torsion, 308  
 Similarity transformation, 53, 62  
 Simpson's rule, 475  
 Singular matrix, 22  
 Skew symmetrical matrix, 11  
 Small strain, 120, 235  
 Small-finite rotation approximation, 238  
 Square matrix, 4  
 Stability of an equilibrium position, 171, 195  
 Stability functions ( $\phi$ ), prismatic member, 589  
 Statically equivalent force system, 103, 106  
 Statically permissible force system, 159, 216, 257  
 Stationary values of a function, 67, 79  
 Stiffness matrix  
   arbitrary curved member, 516, 520  
   modification for partial end restraint, 535  
   prismatic member, geometrically nonlinear behavior, 588, 595  
   prismatic member, linear geometry, 522  
 Strain and complementary energy for pure torsion, 280  
 Strain energy density, 248  
 Stress and strain component transformations, 249  
 Stress components  
   Eulerian, 242  
   Kirchhoff, 246  
 Stress function, torsion, 276  
 Stress resultants and stress couples, 272  
 Stress vector, 240  
 Stress vector transformation, 242  
 Submatrices (matrix partitioning), 12, 36  
 Successive substitution, iterative method  
   member system, 597  
   truss, 193  
 Summary of system equations, force equilibrium and force displacement, 561  
 Symmetrical matrix, 11, 35  
 System stiffness matrix  
   member system, 548, 550, 565  
   truss, 179, 180, 188, 206  
  
 Tangent stiffness matrix  
   for a bar, 193  
   prismatic member, 590, 596  
 Tensor invariants, 232  
 Torsion solution, rectangle, 281  
 Torsional constant,  $J$ , 276, 278, 323  
 Torsional warping function, 274, 377  
 Transverse orthotropic material, 252  
 Transverse shear deformation  
   planar member, 454, 498  
   prismatic member, 355  
 Trapezoidal rule, 474  
 Tree, network, 220  
 Triangular matrix, 12  
 Two-hinged arch solutions, 467, 470  
  
 Unit matrix, 10  
  
 Variable warping parameter,  $f$ , for restrained torsion, 372  
 Vector, definition (mechanics),  $4f_n$   
  
 Work done by a force, definition, 153, 156