

CEE6501 — Lecture 3.1

Local Behavior of an Axial Element

Learning Objectives

By the end of this lecture, you will be able to:

- Define truss DOFs and a consistent sign convention
- Explain local vs global coordinates for an axial member
- Derive the 2×2 local stiffness matrix for an axial element
- Interpret stiffness matrix properties (symmetry, rigid-body mode)
- Describe the idea of flexibility as the inverse relation (preview)
- Formulate the local 4×4 element stiffness matrix (local-only; not transformed)

Agenda

1. Definitions & concepts (DOFs, global vs local)
2. Planar trusses as a model system (DOFs, nodal vectors)
3. Truss stability & determinacy (why statics is not enough)
4. Global and local coordinate systems (notation + sign conventions)
5. Axial element kinematics (local)
6. Axial statics + constitutive relation $\left(\frac{EA}{L} \right)$
7. Local stiffness matrix (2×2)
8. Flexibility formulation (preview)
9. Local 4×4 element stiffness matrix (local; not transformed)
10. Concept checks / mini-examples (McGuire §2.6)

Part 1 — Introductory Definitions & Concepts

Degrees of Freedom (DOFs)

A **degree of freedom (DOF)** is an **independent displacement component** used to describe a structure's motion.

The set of DOFs is the **minimum set of joint displacement components** needed to uniquely describe the deformed configuration under arbitrary loading.

What DOFs Represent

In matrix analysis, DOFs are:

- the **unknown displacement components** we solve for
- the **locations/directions** where nodal loads are applied
- the coordinates used to describe the structure's deformation

Once DOFs are defined, the response is written compactly in matrix form.

DOFs Depend on the Structural Model

The structural model determines **what motion is allowed**:

- **Trusses:** joint translations only
- **Frames:** joint translations **and rotations**
- **Higher-order models:** additional deformation modes

So "DOFs" are not universal — they depend on the assumptions built into the model.

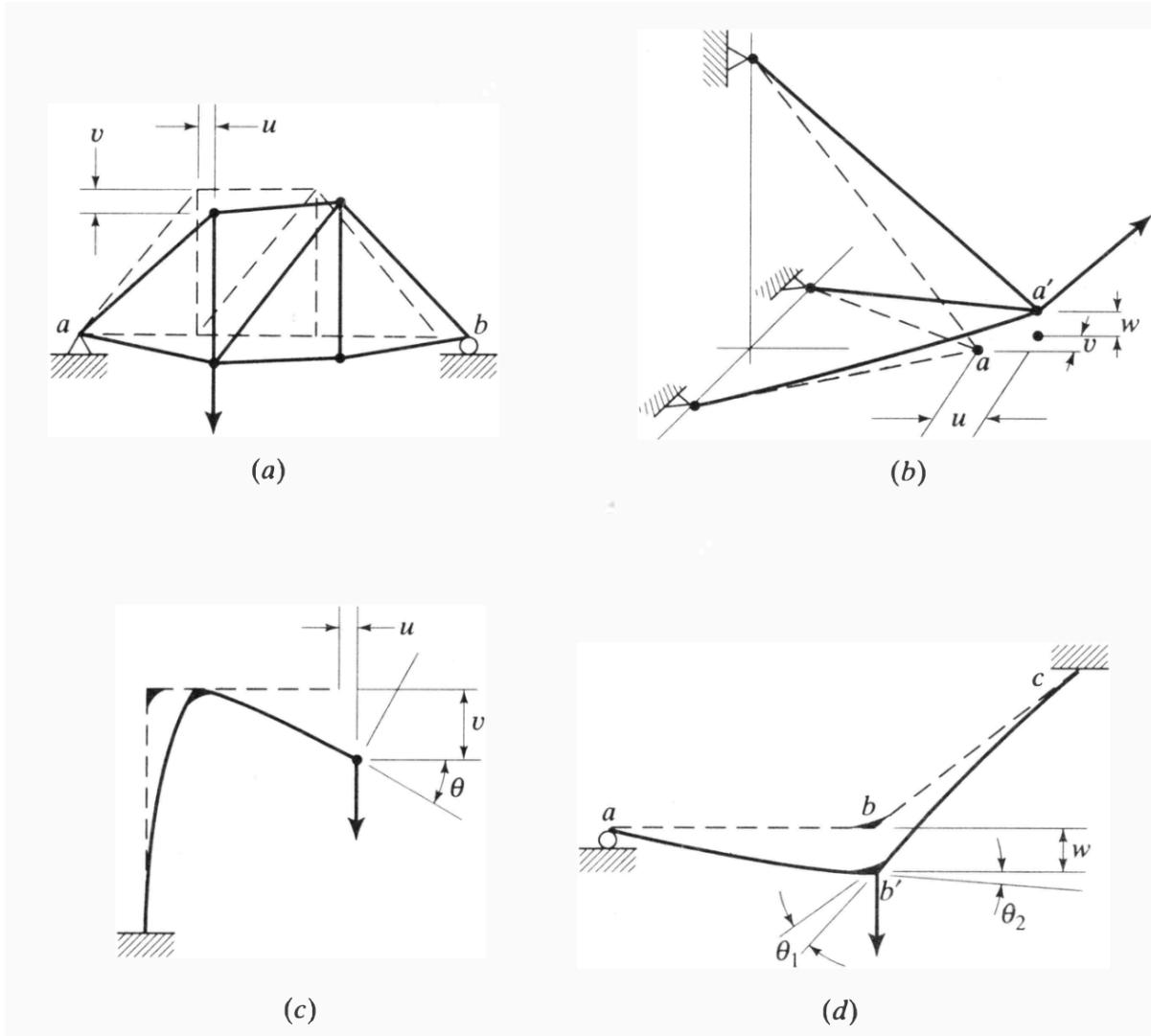


Figure 2.1 Joint displacements. (a) Pin-jointed plane truss. (b) Pin-jointed space truss. (c) Plane frame (in-plane loading). (d) Plane frame (out-of-plane loading).

Global vs Local Viewpoint

In structural analysis we constantly switch between two perspectives:

- **Global:** how the *entire structure* moves and equilibrates
- **Local:** how an *individual element* deforms internally

This distinction is fundamental to the matrix stiffness method.

Global–Local Workflow

The stiffness method follows a consistent pattern:

local element behavior

- assemble to a **global system**
- solve for **global displacements**
- recover **local deformations**
- compute **member forces / stresses**

We solve the structure **globally**, but evaluate and design **locally**.

Notation: Local vs Global

Notation: Global vs Local

We use notation to distinguish viewpoints:

- **Global (structure): u, f, K**
- **Local (element): u', f', k'**

The prime ('') indicates quantities defined in an **element's local coordinate system**.

Part 2 — Planar Trusses as a Structural System

What Is a Plane Truss?

A **plane truss** is a two-dimensional framework of straight members that:

- lie entirely in a single plane
- connect through **frictionless pin joints**
- carry **axial force only** (no bending or shear)
- are loaded only at the joints

Key consequence: each member is in **tension** or **compression** only.

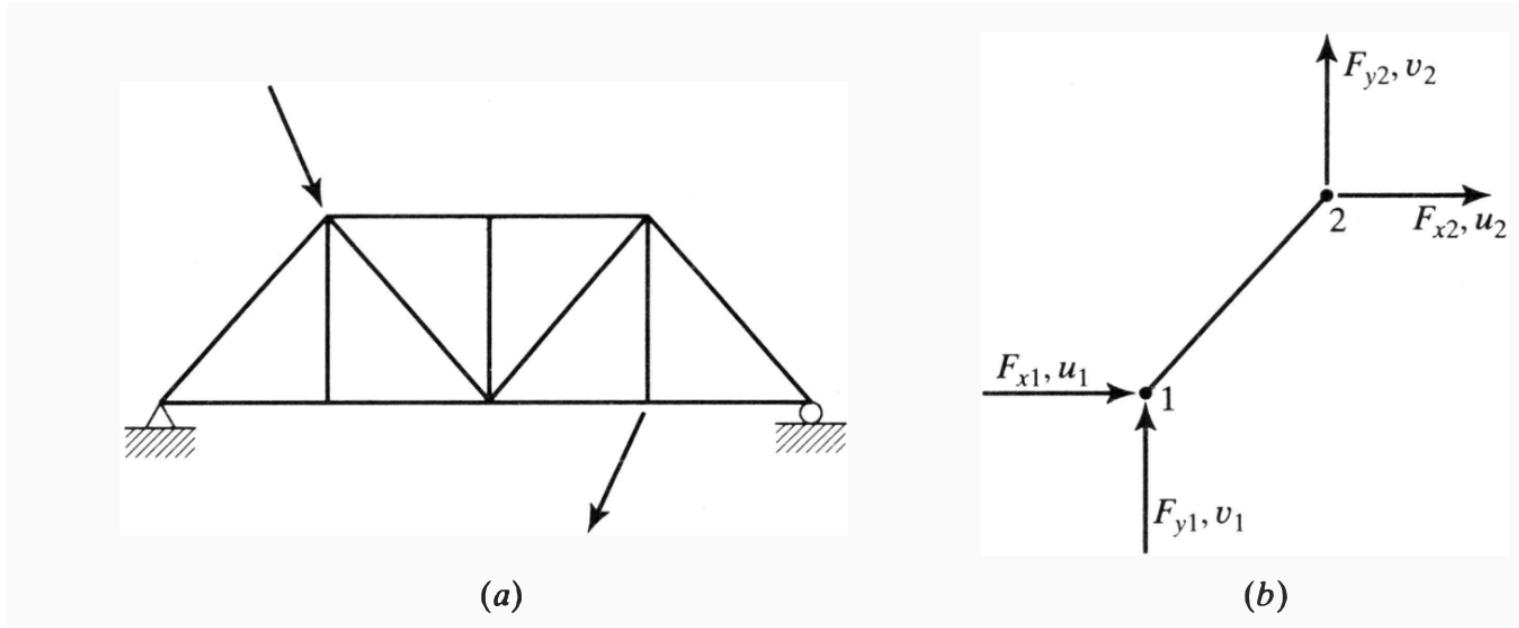


Figure. (a) Idealized planar truss (pin-jointed members). (b) Typical truss member carrying axial force.

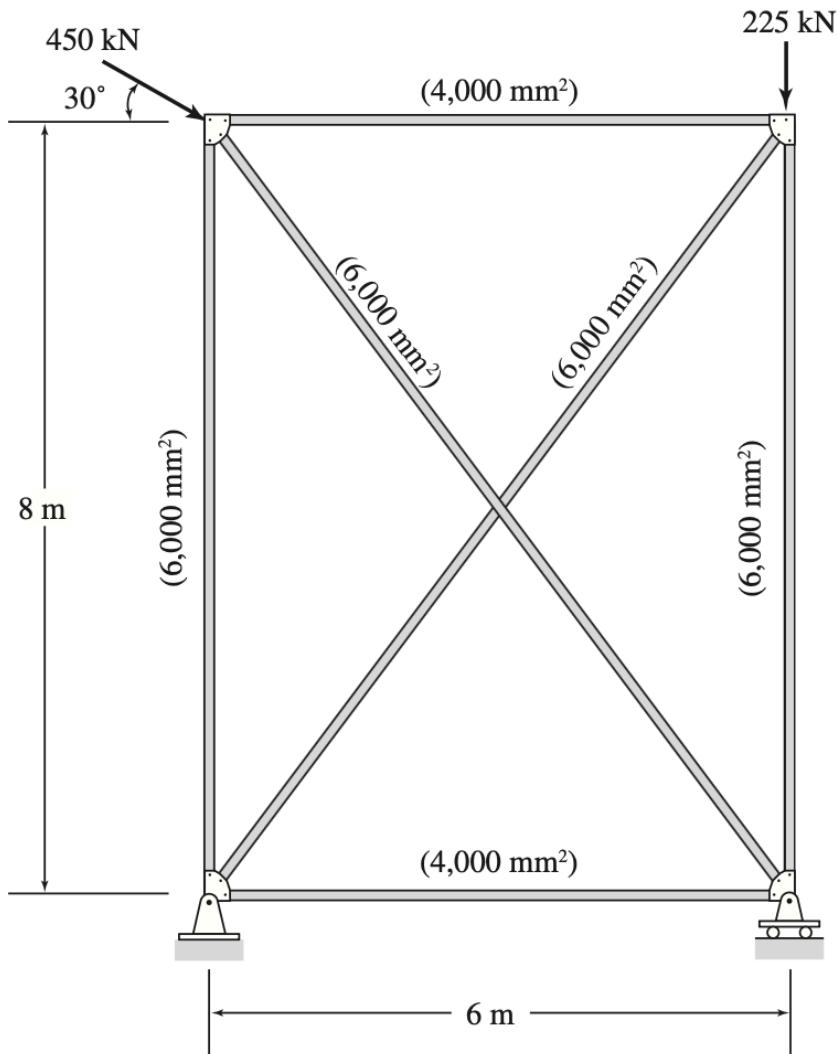


Figure. Idealized planar truss showing member properties, loads, and supports.

Why Trusses Are Ideal for Matrix Analysis

Because members carry **axial force only**:

- Each member behaves like a **1D axial element**
- Force–displacement relations are **linear and simple**
- The local behavior can be derived cleanly and assembled into a system

This makes trusses an excellent first application of the **matrix stiffness method**.

Components of a Truss Analysis Model

A truss analysis (analytical) model has four ingredients:

- **Nodes (joints):** where displacements are defined
- **Elements (members):** connect nodes and carry axial force
- **Supports:** restrain specific displacement components
- **Applied forces:** external loads acting at nodes

What we identify on the line diagram of a truss:

- **Nodes** (circled numbers)
- **Members** (element connectivity between nodes)
- **Applied loads** (known forces at DOF locations)
- **Supports** (restrained displacement components)
- **Free DOFs** (unknown joint translations)

Next we make the DOFs explicit and store them in a displacement vector.

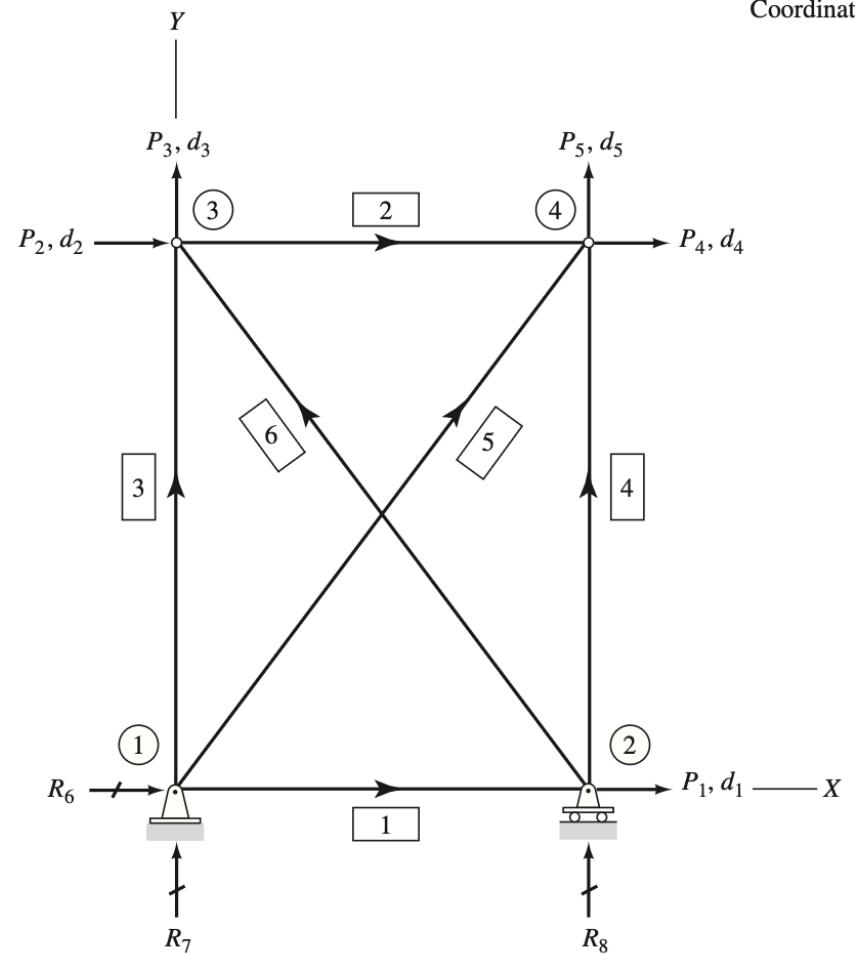


Figure. Components of a planar truss analysis model.

DOFs for a 2D Truss Node

For a planar truss joint, the possible displacement components are:

- u_x — translation in global $+x$
- u_y — translation in global $+y$

Each **free joint** therefore has **two DOFs**.

A truss with j joints has up to $2j$ joint displacement components
(before supports are applied).

Free vs Restrained Joints

Not all joints are free to move.

- **Free joints**
 - displacements are **unknown**
 - contribute DOFs
- **Restrained joints (supports)**
 - displacements are **prescribed** (often zero)
 - remove DOFs

Supports eliminate specific displacement components in x and/or y .

Restrained Degrees of Freedom

Each support restrains one or more displacement components:

- **Pin support**
 - restrains u_x and u_y
 - contributes **2** restraints
- **Roller support**
 - restrains **one** displacement component
 - contributes **1** restraint

We count **restrained displacement components**, not supports.

Let r be the total number of restrained joint displacement components.

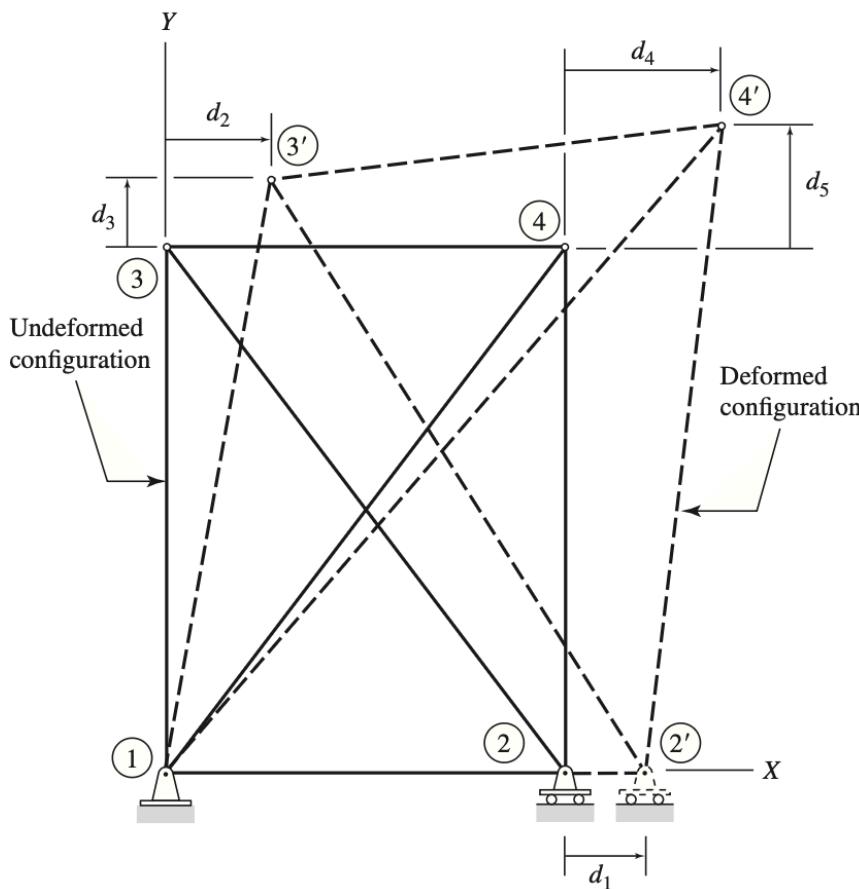


Figure. Truss joint displacements defined in the global coordinate system.

The DOFs are the **independent joint translations** that describe the deformed shape.

- d_1-d_5 are defined in the global $x-y$ system
- Positive directions follow the global axes
- Collect them into a displacement vector $\{d\}$

Structural Vectors: Displacements and Loads

Recall the global equilibrium relation:

$$\mathbf{K} \mathbf{u} = \mathbf{f}$$

In matrix form, we collect the structure's unknowns and knowns into vectors.

Displacement vector

- \mathbf{u} — global displacement vector
 - $\mathbf{d} \rightarrow$ free degrees of freedom (unknown joint displacements)
 - $\mathbf{0} \rightarrow$ restrained degrees of freedom (prescribed displacements)

Force vector

- \mathbf{f} — global force vector
 - $\mathbf{P} \rightarrow$ applied nodal loads at free DOFs
 - $\mathbf{R} \rightarrow$ reaction forces at restrained coordinates

Applied load vector (free DOFs)

$$\mathbf{P} = \{P_1, P_2, P_3, P_4, P_5\}$$

$$= \{0, 389.7, -225, 0, -225\}$$

- $P_1 = 0$
- $P_2 = 389.7$ kN (positive x)
- $P_3 = -225$ kN (negative y)
- $P_4 = 0$
- $P_5 = -225$ kN (negative y)

Each load component corresponds directly to a numbered **degree of freedom**.

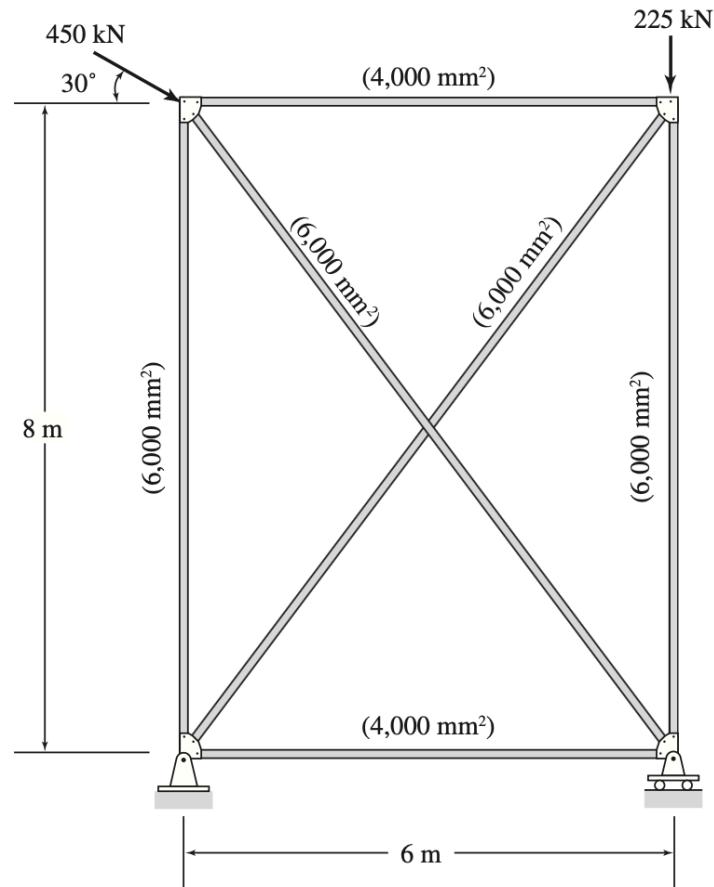
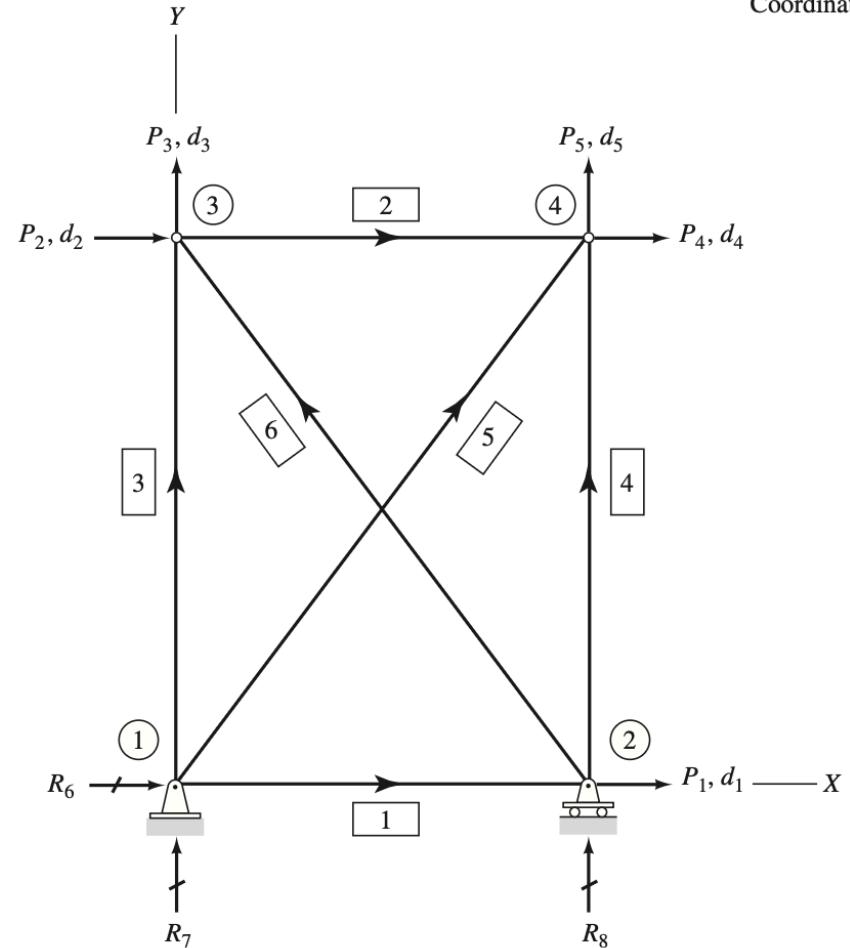


Figure. Applied nodal loads.

Coordinate



The global equilibrium is written as:

$$\mathbf{K} \begin{Bmatrix} d_1 \\ d_2 \\ d_3 \\ d_4 \\ d_5 \\ 0 \\ 0 \\ 0 \end{Bmatrix} = \begin{Bmatrix} 0 \\ 389.7 \\ -225 \\ 0 \\ -225 \\ R_6 \\ R_7 \\ R_8 \end{Bmatrix} \text{ kN}$$

Components of a planar truss analysis model.

In-Class Exercise - Structural Vectors

1. **Number the joints** (nodes) on the figure.
 2. **Number the members** (elements).
 3. **Assign global DOF numbers** at each node.
 4. **Identify DOF types:**
 - *Circle* free (unknown) DOFs
 - *Box* DOFs with applied loads
 - *Underline* restrained DOFs (reaction forces)
 5. **Write the global displacement vector $\{u\}$.**
 6. **Write the global force vector $\{f\}$.**
- (Based on your DOF numbering; use variables where unknown and insert known values where prescribed.)*

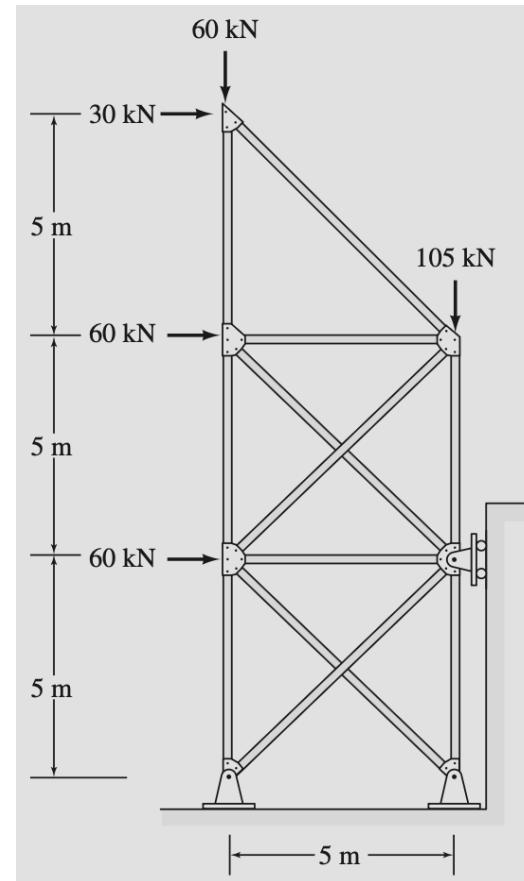


Figure. Truss structure.

Answers — Structural Vectors

$$\boldsymbol{u} = \begin{Bmatrix} 0 \\ 0 \\ 0 \\ 0 \\ u_5 \\ u_6 \\ 0 \\ u_8 \\ u_9 \\ u_{10} \\ u_{11} \\ u_{12} \\ u_{13} \\ u_{14} \end{Bmatrix} \quad \boldsymbol{f} = \begin{Bmatrix} r_1 \\ r_2 \\ r_3 \\ r_4 \\ 60 \\ 0 \\ r_7 \\ 0 \\ 60 \\ 0 \\ 0 \\ -105 \\ 30 \\ 60 \end{Bmatrix}$$

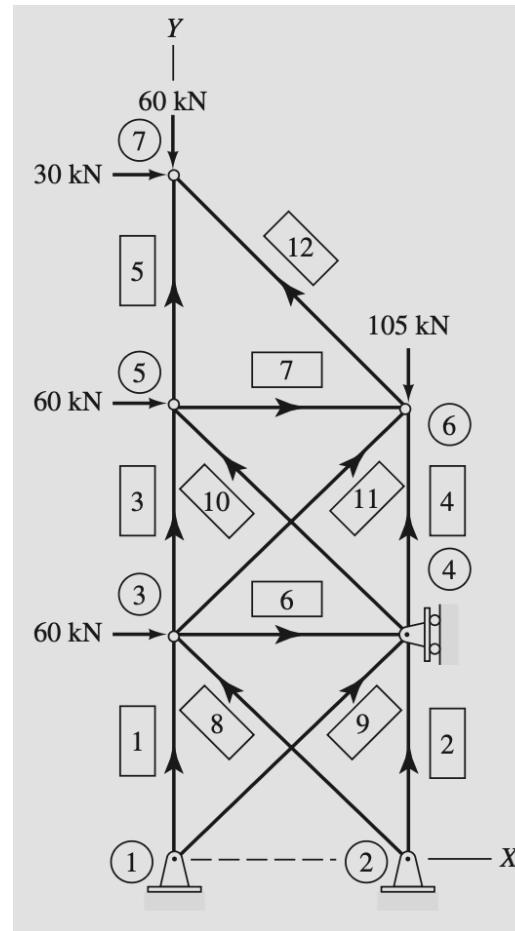


Figure. Truss structure numbered.

Part 3 - Truss Stability and Determinacy

Counting Degrees of Freedom

Let:

- j = number of joints
- r = number of restrained joint displacement components
- N_{CJT} = DOFs per free joint

Then the number of structural degrees of freedom is:

$$N_{DOF} = N_{CJT} j - r$$

DOFs for a Planar Truss

For a planar truss, each free joint has two translational DOFs:

$$N_{CJT} = 2 \quad (u_x, u_y)$$

So:

$$N_{DOF} = 2j - r$$

This is the number of **independent joint displacements** that must be solved for.

Stability vs Static Determinacy

- **Stability:** does the structure prevent rigid-body motion?
- **Static determinacy:** can forces be found from equilibrium alone?

These are related, but **not the same**.

We will separate:

- **stability** (rigid-body motion)
- **external determinacy** (reactions from global equilibrium)
- **internal determinacy** (member forces from joint equilibrium)

Stability Requirement (Rigid-Body Motion)

A free planar structure has **three rigid-body motions**:

- translation in x
- translation in y
- rotation in the plane

To prevent rigid-body motion, the supports must restrain at least:

$$r \geq 3$$

This is a **stability requirement**, not a determinacy condition.

- **Stability** asks whether the structure can resist rigid-body motion and admit an equilibrium configuration.
- **Determinacy** is a separate question, asked **only after stability is ensured**, and concerns whether forces can be found from equilibrium alone.

Global Equilibrium (What Statics Provides)

For a planar structure, global equilibrium provides **three equations**:

- $\sum F_x = 0$
- $\sum F_y = 0$
- $\sum M = 0$

These equations apply to the **entire structure** treated as a rigid body.

They govern **reaction forces only** (external equilibrium).

External (Global) Static Indeterminacy

Let r be the number of reaction components.

Global equilibrium provides **3 equations** in 2D.

So if:

$$r > 3$$

then reactions cannot be determined from statics alone.

The structure is **externally statically indeterminate**.

Internal Static Determinacy for a Planar Truss (Counting)

At each joint, equilibrium gives two equations:

$$\sum F_x = 0, \quad \sum F_y = 0$$

Across j joints, that is **$2j$ joint equilibrium equations**.

Unknown forces are:

- m member axial forces
- r reaction components

A necessary counting condition for solving forces by equilibrium is thus:

$$m + r = 2j$$

Interpreting the Internal Counting Condition

The comparison

$$m + r \quad \text{vs.} \quad 2j$$

compares **unknown forces** to **joint equilibrium equations**:

- $m + r < 2j$
→ **unstable / mechanism** (not enough constraints; a deformation mode exists)
- $m + r = 2j$
→ **statically determinate by counting** (*if geometry is stable*)
- $m + r > 2j$
→ **statically indeterminate by counting** (redundant member/support forces)

This is a **counting test** — it does not guarantee stability.

What the Counting Condition Does *Not* Guarantee

Counting compares equations and unknowns, but it does **not**:

- detect rigid-body motion
- detect geometric mechanisms
- guarantee a unique solution

So passing a counting test is **necessary**, not sufficient.

Possible Outcomes

A structure can therefore be:

- **Stable but statically indeterminate**
 - stable (no rigid-body motion)
 - but has redundancies: $m + r > 2j$ or $r > 3$
 - forces depend on deformation compatibility
- **Unstable but satisfy $m + r = 2j$**
 - the count matches, but the geometry forms a mechanism
 - equilibrium equations exist, but the structure can move without resistance

Why the Direct Stiffness Method is Powerful

Equilibrium alone does **not** enforce compatibility.

The Direct Stiffness Method solves by enforcing:

- equilibrium at joints
- compatibility of joint displacements
- member force–deformation relations

We can still solve indeterminate cases when:

$$r > 3 \quad \text{or} \quad m + r > 2j$$

If a structure is **unstable**, it appears as a **singular stiffness matrix \mathbf{K}** .

In-Class Exercise — Stability & Determinacy

Questions (work in pairs):

1. How many **joints** (j) does this structure have?
2. How many **members** (m) are present?
3. How many **reaction components** (r) are provided by the supports?
4. Does the structure satisfy the **stability requirement**?
5. Based on counting, is the structure **statically determinate or indeterminate**?
6. If indeterminate, is the indeterminacy **external, internal, or both**?

No force calculations — focus on counting and concepts.

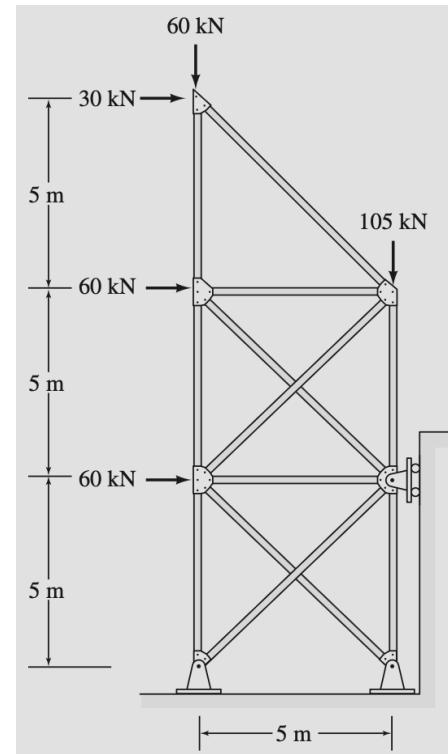


Figure. Truss used for stability and determinacy assessment.

 Answers — Stability & Determinacy

- **Number of joints:** $j = 7$:
- **Number of members:** $m = 12$:
- **Number of reaction components** $r = 2 + 2 + 1 = 5$:
- **Stability requirement:**
For a planar structure, external stability requires

$$r \geq 3$$

Since $5 \geq 3$, the structure **is stable**.

- **Static determinacy (counting test):**

For a planar truss, compare

$$m + r \quad \text{and} \quad 2j$$

$$m + r = 12 + 5 = 17, \quad 2j = 2(7) = 14$$

Since ($17 > 14$), the structure is **statically indeterminate**.

- **Type of indeterminacy:**

- Total indeterminacy:

$$D_t = m + r - 2j = 3$$

- External indeterminacy:

$$D_e = r - 3 = 2$$

- Internal indeterminacy:

$$D_i = D_t - D_e = 1$$

- 👉 The structure is **indeterminate both externally and internally**.

External indeterminacy

There are **more reaction components than required for global equilibrium**, so the support reactions cannot be determined using statics alone.

Internal indeterminacy

The structure contains **more members than are required for equilibrium**, meaning at least one **redundant load path** exists and some member forces cannot be found using statics alone.

Another way to think about indeterminacy:

Indeterminacy often means there is **more than one load path** available for forces to travel through the structure.

How the load is shared between these paths depends on **stiffness and deformation compatibility**, not just equilibrium.

- ✓ This is **not a problem** for the **Direct Stiffness Method**: stiffness-based formulations resolve redundancy automatically by enforcing **compatibility and equilibrium simultaneously**.

Part 4 — Global and Local Coordinate Systems

Why Local Coordinates?

Local coordinates simplify element behavior:

- axial deformation occurs **along the member axis**
- stress–strain relations are simplest in that direction
- local coordinates separate **element behavior** from **global geometry**

Coordinate and Sign Conventions

- Global axes: $+x$ to the right, $+y$ upward
- Positive axial force: **tension**
- Local $+x'$ axis: defined from **start node** to **end node**

Consistent conventions are essential for correct assembly.

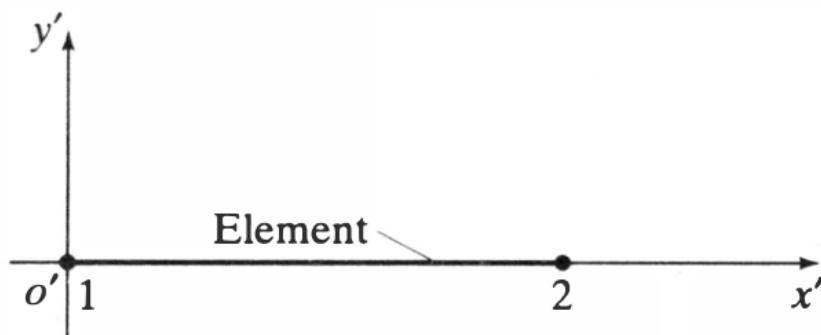
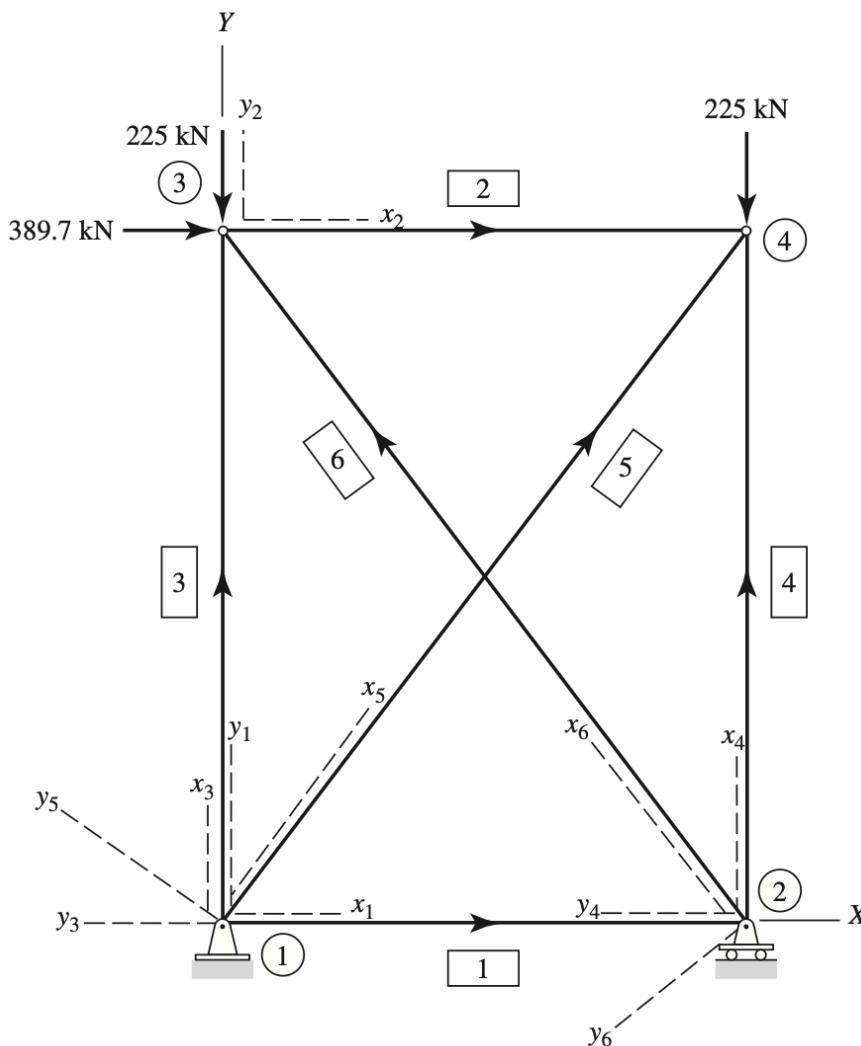


Figure. Definition of local element axis.



Each truss member is assigned its own **local coordinate system**.

- The local axis x' is aligned with the member
- The positive direction is defined from start node to end node
- Axial deformation and force are expressed in this system

Figure. Local element axes superimposed on a truss structure.

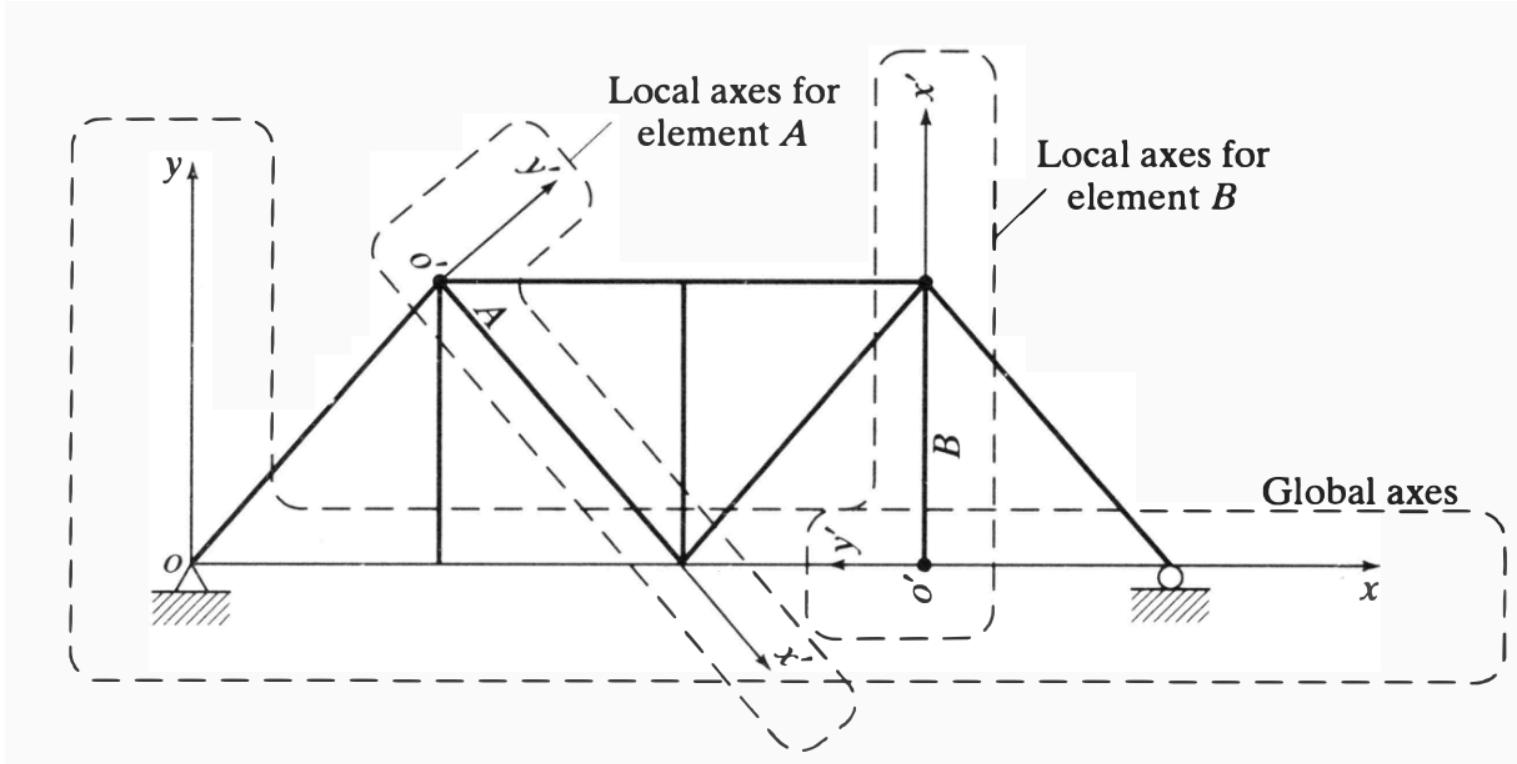


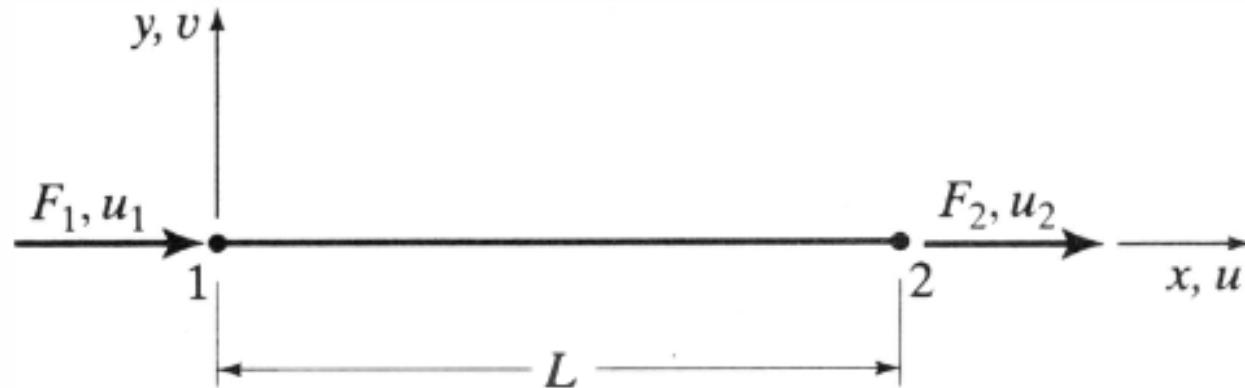
Figure. Relationship between global and local coordinate systems.

Part 5 — Axial Element Kinematics (Local)

Axial truss element (local view)

- Straight, prismatic truss member
- Length L , area A , Young's modulus E
- Two nodes define the element: node 1 and node 2
- Two **local axial DOFs**: u_1 and u_2 (one at each node)
- Local x axis is aligned with the member (positive to the right)

Local degrees of freedom



- Axial displacement at node 1: u_1
- Axial displacement at node 2: u_2

In this section: axial DOFs only (u_1, u_2).

Note: transverse DOFs (v_1, v_2) appear later when we build the full 4×4 local truss matrix.

Axial kinematics

The axial deformation is the relative displacement of the ends:

$$\delta = u_2 - u_1$$

- If $u_2 > u_1$ then $\delta > 0 \rightarrow \text{elongation (tension)}$
- If $u_2 < u_1$ then $\delta < 0 \rightarrow \text{shortening (compression)}$

Free-body diagram (axial)

- Axial end force at node 1: F_1
- Axial end force at node 2: F_2

Equilibrium along the member axis:

$$\sum F_x = 0$$

- ➡ The end forces are equal and opposite.

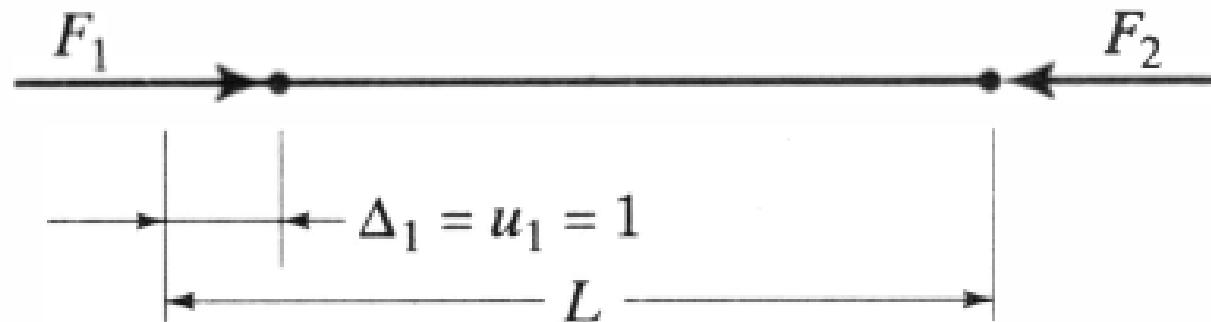
Kinematics examples (what do δ and F look like?)

Compression example: $u_1 = 1, u_2 = 0$

$$\delta = 0 - 1 = -1 < 0 \quad \Rightarrow \text{compression}$$

Take positive as pointing to the right:

$$+F_1 - F_2 = 0 \quad \Rightarrow \quad F_1 = F_2$$

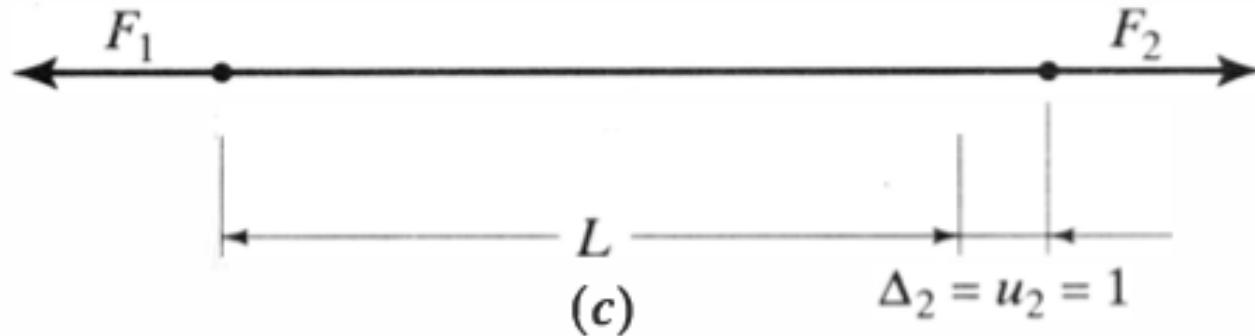


Tension example: $u_1 = 0, u_2 = 1$

$$\delta = 1 - 0 = 1 > 0 \Rightarrow \text{tension}$$

Take positive as pointing to the right:

$$-F_1 + F_2 = 0 \Rightarrow F_1 = F_2$$



Part 6 — Deriving 2x2 Stiffness Matrix

Axial constitutive law (linear elasticity)

Hooke's law (uniaxial, linear elastic):

$$E = \frac{\sigma}{\varepsilon}$$

Strain (Engineering strain, small deformation, $L = 0$):

$$\varepsilon = \frac{\delta}{L} = \frac{u_2 - u_1}{L}$$

Stress definition:

$$\sigma = \frac{F}{A}$$

Axial force:

$$F = \frac{EA}{L}(u_2 - u_1)$$

Notes: In geometric nonlinearity, the "L" and kinematics change; in material nonlinearity, the σ - ε law changes.

End forces in terms of u_1, u_2

Using the same sign convention (positive to the right):

$$F_1 = \frac{EA}{L}(u_1 - u_2)$$

- If $u_1 > u_2$ (compression), then $F_1 > 0$ ($F_2 < 0$)

$$F_2 = \frac{EA}{L}(u_2 - u_1)$$

- If $u_2 > u_1$ (tension), then $F_2 > 0$ ($F_1 < 0$)

Local axial stiffness matrix (2×2)

Multiply out the end-force equations:

$$F_1 = \frac{EA}{L} \cdot u_1 - \frac{EA}{L} \cdot u_2$$

$$F_2 = -\frac{EA}{L} \cdot u_1 + \frac{EA}{L} \cdot u_2$$

Collect in matrix form:

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} u_1 \\ u_2 \end{Bmatrix}$$

Scenario 1 (unit displacement): $u_1 = 1, u_2 = 0$

$$\delta = u_2 - u_1 = 0 - 1 = -1 \quad (\text{compression})$$

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} 1 \\ 0 \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} 1 \\ -1 \end{Bmatrix}$$

So:

$$F_1 = +EA/L$$

$$F_2 = -EA/L$$

This matches the "compression example" we looked at in Part 5

Scenario 2: $u_1 = 5, u_2 = 3$

$$\delta = u_2 - u_1 = 3 - 5 = -2 \quad (\text{compression})$$

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} 5 \\ 3 \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} 2 \\ -2 \end{Bmatrix}$$

So:

$$F_1 = +2EA/L$$

$$F_2 = -2EA/L$$

Double the amount of strain, double the amount of force.

Scenario 3: $u_1 = 1, u_2 = -1$

$$\delta = u_2 - u_1 = -1 - 1 = -2 \quad (\text{compression})$$

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} 1 \\ -1 \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} 2 \\ -2 \end{Bmatrix}$$

So:

$$F_1 = +2EA/L$$

$$F_2 = -2EA/L$$

Same relative deformation ($\delta = -2$) \Rightarrow same end-force pattern.

Scenario 4: $u_1 = -2, u_2 = -1$

$$\delta = u_2 - u_1 = -1 - (-2) = +1 \quad (\text{tension})$$

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} -2 \\ -1 \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} -1 \\ 1 \end{Bmatrix}$$

So:

$$F_1 = -EA/L$$

$$F_2 = +EA/L$$

Same example we looked at in Part 5, tension where $u = 1$.

Scenario 5 (rigid-body translation): $u_1 = 3, u_2 = 3$

$$\delta = u_2 - u_1 = 3 - 3 = 0 \quad (\text{no deformation})$$

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} 3 \\ -3 \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} 0 \\ 0 \end{Bmatrix}$$

So:

$$F_1 = 0$$

$$F_2 = 0$$

*Rigid translation produces **no internal axial force**.*

In [17]:

```
# Axial 2x2 stiffness: one editable scenario
import numpy as np

# Choose stiffness scale (set EA_over_L = 1 for clean numbers)
EA_over_L = 1.0
k = EA_over_L * np.array([[1.0, -1.0],
                           [-1.0, 1.0]])

# --- Edit these ---
u1 = 1.0
u2 = 0.0

u = np.array([u1, u2])
f = k @ u
delta = u2 - u1

state = "tension" if delta > 0 else ("compression" if delta < 0 else "ri

# print("k =\n", k)
print(f"u = [u1, u2] = {u}")
print(f"delta = u2 - u1 = {delta} -> {state}")
print(f"f = [F1, F2] = {f}")


```

```
u = [u1, u2] = [1. 0.]
delta = u2 - u1 = -1.0 -> compression
f = [F1, F2] = [ 1. -1.]
```

IMPORTANT: Definition of a stiffness coefficient k_{ij}

k_{ij} = force at DOF i due to a unit displacement at DOF j ,
with all other DOFs held fixed.

$$\begin{bmatrix} k_{11} & k_{12} \\ k_{21} & k_{22} \end{bmatrix}$$

Here we only have 2 DOFs. Later (beams / frames), this interpretation becomes more important.

Unit displacement construction of columns

Each column of the stiffness matrix is built by:

- Impose a **unit displacement** at one DOF
- Hold all the other DOF fixed
- Record the resulting nodal force pattern

This suppresses rigid-body motion while defining the columns.

Unit displacement interpretation — Column 1

$$\begin{bmatrix} k_{11} & k_{12} \\ k_{21} & k_{22} \end{bmatrix}$$

k_{11} :

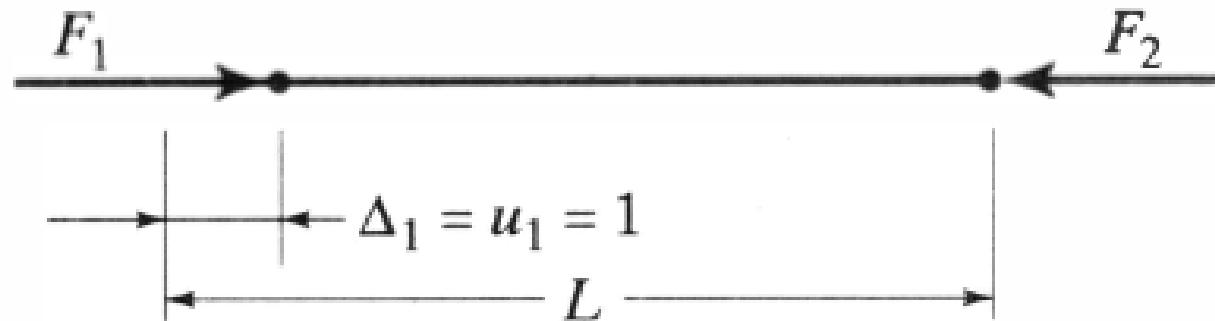
- $i = 1, j = 1$
- $i = 1$: force at DOF 1
- $j = 1$: due to a unit displacement at DOF 1 ($u_1 = 1$)
- all other displacements are 0 (i.e., $u_2 = 0$)

k_{21} :

- $i = 2, j = 1$
- $i = 2$: force at DOF 2
- $j = 1$: due to a unit displacement at DOF 1 ($u_1 = 1$)
- all other displacements are 0 (i.e., $u_2 = 0$)

Unit displacement interpretation — Column 1

Impose $u_1 = 1, u_2 = 0$:



$$k_{11} = +\frac{EA}{L} \quad \text{and} \quad k_{21} = -\frac{EA}{L}$$

Unit displacement interpretation — Column 2

$$\begin{bmatrix} k_{11} & \boxed{k_{12}} \\ k_{21} & \boxed{k_{22}} \end{bmatrix}$$

k_{12} :

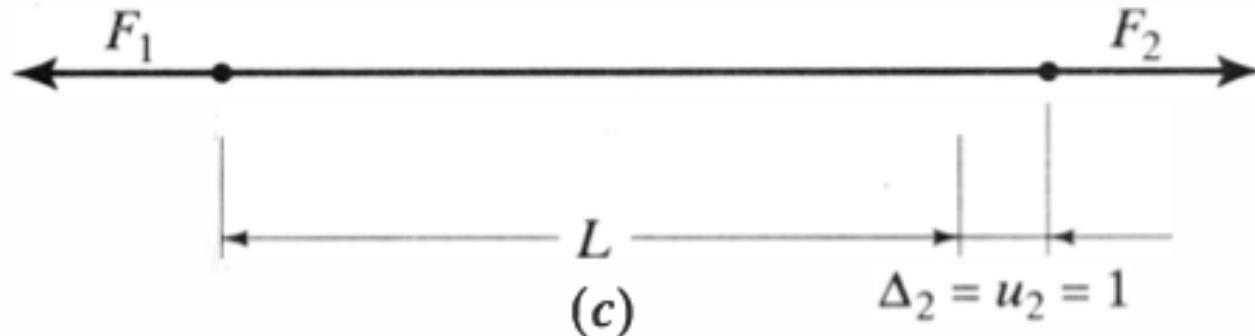
- $i = 1, j = 2$
- $i = 1$: force at DOF 1
- $j = 2$: due to a unit displacement at DOF 2 ($u_2 = 1$)
- all other displacements are 0 (i.e., $u_1 = 0$)

k_{22} :

- $i = 2, j = 2$
- $i = 2$: force at DOF 2
- $j = 2$: due to a unit displacement at DOF 2 ($u_2 = 1$)
- all other displacements are 0 (i.e., $u_1 = 0$)

Unit displacement interpretation — Column 2

Impose $u_1 = 0, u_2 = 1$:



$$k_{12} = -\frac{EA}{L} \quad \text{and} \quad k_{22} = +\frac{EA}{L}$$

Equilibrium and column sums

$$\mathbf{k}_e = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix}$$

Check each column is self-equilibrated:

$$\sum F_x = 0$$

- The entries in each column sum to zero.

Symmetry (reciprocity)

$$k_{12} = k_{21} = -\frac{EA}{L}$$

- **Case 1 (k_{12}):** response to $u_2 = 1$ (with $u_1 = 0$)
→ the element is **stretched**, producing a negative force (left) at DOF 1
- **Case 2 (k_{21}):** response to $u_1 = 1$ (with $u_2 = 0$)
→ the element is **compressed**, producing a negative force (left) at DOF 2

In both cases, the magnitude of the resisting force is the same.

Mathematically, this follows from **energy reciprocity**:
the work done by DOF 1 on DOF 2 equals the work done by DOF 2 on DOF 1.

➡ Symmetry reflects that the element's response depends only on relative deformation, not on which end is displaced.

Why the element stiffness matrix is singular?

$$\det(\mathbf{k}_e) = 0$$

Matrix meaning: there is some **nonzero/non-trivial displacement vector** that produces **zero force**.

Physical meaning: the element alone is not anchored — it can undergo **rigid-body translation** (we showed this in scenario 5)

This is not a problem at the local level: stability is enforced only when we assemble the **full structure** and apply supports in the form of DOF restraints.

Rigid-body motion (worked out)

Let $u_1 = u_2 = c$:

$$\begin{Bmatrix} F_1 \\ F_2 \end{Bmatrix} = \frac{EA}{L} \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \begin{Bmatrix} c \\ c \end{Bmatrix} = \frac{EA}{L} \begin{Bmatrix} c - c \\ -c + c \end{Bmatrix} = \begin{Bmatrix} 0 \\ 0 \end{Bmatrix}$$

➡ No internal force unless there is **relative displacement**, translation to the right.

Key takeaways

- The 2×2 axial stiffness matrix enforces **equilibrium + compatibility** at the element level
 - Symmetry reflects **reciprocity** ($k_{12} = k_{21}$)
 - Singularity reflects **rigid-body freedom** (no force if $u_1 = u_2$)
 - Supports/constraints are applied at the **global structure level**, not the element level
- ➡ This 2×2 matrix is the fundamental building block of truss stiffness assembly.

Part 8 — Flexibility Formulation (Preview)

Draft note (delete later): flexibility formulation, why important, will we use?

Stiffness viewpoint:

$$\{f\} = [k]\{u\}$$

Flexibility viewpoint (inverse mapping):

$$\{u\} = [f]\{f\}$$

Why it matters:

- Leads to compatibility-based methods
- Useful for interpretation

In this course, we primarily use stiffness-based methods.

Part 9 — Local 4×4 Stiffness Matrix (Local-Only)

Draft note (delete later): formulate the 4×4 matrix in local (many zeros); more generic case (Kassimali §3.3); full derivation

For a planar truss member, describe the element DOFs in the local coordinate system:

$$\{u\}_e^{(local)} = [u_{1x'}, u_{1y'}, u_{2x'}, u_{2y'}]^T$$

In an ideal truss member, only the axial DOFs (x' direction) create axial strain. That means the element stiffness only couples $u_{1x'}$ and $u_{2x'}$.

Embed the 2×2 axial stiffness into a 4-DOF local description:

$$[k]_e^{(local)} = \frac{EA}{L} \begin{bmatrix} 1 & 0 & -1 & 0 \\ 0 & 0 & 0 & 0 \\ -1 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix}$$

Interpretation:

- The zeros reflect that the truss element provides no stiffness in y' .
- The 4×4 form matches the 2 DOFs per node bookkeeping used later for assembly.

Part 10 — Concept Checks / Mini-Examples (McGuire §2.6)

Draft note (delete later): examples of non-matrix structural analysis truss problems using these concepts (McGuire §2.6)

Check A: Given E , A , L and u'_1 , u'_2 , compute δ , N , f'_1 , f'_2 .

Check B: If EA/L doubles, what happens to end forces for the same $\{u'\}$?

Check C: What displacement pattern produces zero force, and why?

Check D: In the local 4×4 matrix, which DOFs are inactive, and what physical assumption causes that?

```
In [16]: # (Optional) Mini-example code stub
# Define E, A, L, and local nodal displacements u1p, u2p

import numpy as np

E = None
A = None
L = None
u1p = None
u2p = None

# Local 2x2 stiffness
# k2 = (E*A/L) * np.array([[1, -1], [-1, 1]])
k2 = None

# TODO: compute f' = k2 * u'
u_local = None
f_local = None

k2, u_local, f_local
```

```
Out[16]: (None, None, None)
```

Looking Ahead

→ Next (Lecture 3.2):

- Build the transformation matrix from local to global
- Rotate element stiffness into global coordinates
- Assemble the global stiffness matrix for a truss
- Apply supports, solve for displacements, and recover member forces