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**A port-Hamiltonian formulation of flexible structures
Modelling and symplectic finite element discretization**

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Abstract

3 This thesis aims at extending the port-Hamiltonian (pH) approach to continuum mechanics
 4 in higher geometrical dimensions (particularly in 2D). The pH formalism has a strong mul-
 5 tiphysics character and represents a unified framework to model, analyze and control both
 6 finite- and infinite-dimensional systems. Despite the large literature on this topic, elasticity
 7 problems in higher geometrical dimensions have almost never been considered. This work
 8 establishes the connection between port-Hamiltonian distributed systems and elasticity prob-
 9 lems. The originality resides in three major contributions. First, the novel pH formulation
 10 of plate models and coupled thermoelastic phenomena is presented. The use of tensor cal-
 11 culus is mandatory for continuum mechanical models and the inclusion of tensor variables is
 12 necessary to obtain an intrinsic, i.e. coordinate free, and equivalent pH description. Second,
 13 a finite element based discretization technique, capable of preserving the structure of the
 14 infinite-dimensional problem at a discrete level, is developed and validated. The discretiza-
 15 tion of elasticity problems in port-Hamiltonian form requires the use of non-standard finite
 16 elements. Nevertheless, the numerical implementation is performed thanks to well-established
 17 open-source libraries, providing external users with an easy to use tool for simulating flexible
 18 systems in pH form. Third, flexible multibody systems are recast in pH form by making use of
 19 a floating frame description valid under small deformations assumptions. This reformulation
 20 include all kinds of linear elastic models and exploits the intrinsic modularity of pH systems.

Résumé

22 Cette thèse vise à étendre l'approche port-Hamiltonienne (pH) à la mécanique des milieux
 23 continus dans des dimensions géométriques plus élevées (en particulier on se focalise sur la
 24 dimension deux). Le formalisme pH, avec son fort caractère multiphysique, représente un
 25 cadre unifié pour modéliser, analyser et contrôler les systèmes de dimension finie et infinie.
 26 Malgré l'abondante littérature sur ce sujet, les problèmes d'élasticité en deux ou trois dimen-
 27 sions géométriques n'ont presque jamais été considérés. Dans ce travail de thèse la connexion
 28 entre problèmes d'élasticité et systèmes distribués port-Hamiltoniens est établie. L'originalité
 29 apportée réside dans trois contributions majeures. Tout d'abord, une nouvelle formula-
 30 tion pH des modèles de plaques et des phénomènes thermoélastiques couplés est présen-
 31 tée. L'utilisation du calcul tensoriel est obligatoire pour modéliser les milieux continus et
 32 l'introduction de variables tensorielles est nécessaire pour obtenir une description pH équiva-
 33 lente qui soit intrinsèque, c'est-à-dire indépendante des coordonnées choisies. Deuxièmement,
 34 une technique de discrétisation basée sur les éléments finis et capable de préserver la structure
 35 du problème de la dimension infinie au niveau discret est développée et validée. La discrési-
 36 sation des problèmes d'élasticité écrits en forme port-Hamiltonienne nécessite l'utilisation
 37 d'éléments finis non standards. Néanmoins, l'implémentation numérique est réalisée grâce
 38 à des bibliothèques open source bien établies, fournissant aux utilisateurs externes un outil
 39 facile à utiliser pour simuler des systèmes flexibles sous forme pH. Troisièmement, une nou-
 40 velle formulation pH de la dynamique multicorps flexible est dérivée. Cette reformulation,
 41 valable sous de petites hypothèses de déformations, inclut toutes sortes de modèles élastiques
 42 linéaires et exploite la modularité intrinsèque des systèmes pH.

Acknowledgments

Remerciements

Ringraziamenti

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List of Acronyms

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179	DAE	<i>Differential-Algebraic Equation</i>
180	dpHs	<i>distributed port-Hamiltonian systems</i>
181	FEM	<i>Finite Element Method</i>
182	IDA-PBC	<i>Interconnection and Damping Assignment Passivity Based Control</i>
183	PDE	<i>Partial Differential Equation</i>
184	PFEM	<i>Partitioned Finite Element Method</i>
185	pH	<i>port-Hamiltonian</i>
186	pHs	<i>port-Hamiltonian systems</i>
187	pHDAE	<i>port-Hamiltonian Descriptor System</i>

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Part I

Introduction and state of the art

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Introduction

I was born not knowing and have had only a little time to change that
here and there.

Richard Feynman
Letter to Armando Garcia J.

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- 1.1 Motivation and context**
- 1.2 Overview of chapters**
- 1.3 Contributions**

Literature review

Books serve to show a man that those original thoughts of his aren't very new after all.

Abraham Lincoln

2.1 Port-Hamiltonian distributed systems

Differential geometry An interesting reference that can provide some ideas in this direction is [Yao11, NY04].

For 1D linear PH systems with a generalized skew-adjoint system operator, [LGZM05] gives conditions on the assignment of boundary inputs and outputs for the system operator to generate a contraction semigroup. The latter is instrumental to show well-posedness of a linear PH system, see [JZ12]. Essentially, at most half the number of boundary port variables can be imposed as control inputs for a well-posed PH system in one-dimensional domains. The complete characterization of pH in arbitrary dimension is still an open research field. Two notable exceptions [KZ15, Skr19] provide partial answers to this problem. The first demonstrate the well-posedness of the linear wave equation in arbitrary geometrical dimensions. The second generalizes this result to treat the case of generic first order linear pHs in arbitrary geometrical dimensions.

2.2 Structure-preserving discretization

2.3 Mixed finite element for elasticity

Thanks to [?], it has become evident that there is a strict link between discretization of port-Hamiltonian (pH) systems and mixed finite elements. Velocity-stress formulation for the wave dynamics and elastodynamics problems are indeed Hamiltonian and their mixed discretization preserves such a structure. For instance in [KK15] the authors employed mixed finite elements to obtain a symplectic semi-discretization for the wave equation. This allows using known finite element scheme to preserve the pH structure at the discrete level.

232 Mixed finite elements for the wave equation have been studied in [Gev88, BJT00]. For
233 elastodynamics the construction of stable elements gets more complicated because of the
234 presence of the symmetric stress tensor. Existing elements enforce symmetry either strongly
235 [BJT01] or weakly [AL14].

236 2.4 Multibody dynamics

Reminder on port-Hamiltonian systems

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The main mathematical aspects behind the pH formalism are recalled in this chapter. First, the finite dimensional case is considered. The geometric concept of Dirac structure [Cou90] is first presented. Finite dimensional port-Hamiltonian system are then introduced by making clear their intimate connection with the concept of Dirac structure. Second, the infinite dimensional case is recalled. The equivalent of Dirac structures for the infinite-dimensional case is the concept of Stokes-Dirac structure. Analogously to what happens in the finite-dimensional case, infinite-dimensional (or distributed) port-Hamiltonian systems are intimately related to the concept of Stokes-Dirac structure.

This notion of Stokes-Dirac structure was first introduced in the literature by making use of a differential geometry approach [vdSM02]. Despite being really insightful in terms of geometrical structure, this approach does not encompass the case of higher-order differential operators. An extension in this sense is still an open question. Since bending problems in elasticity introduce higher-order differential operators, the language of PDE will be privileged over the one of differential forms.

3.1 Finite dimensional setting

Finite dimensional port-Hamiltonian are characterized by geometrical structures called Dirac structures. It is important to define this geometric concept and see how pHs relate to it.

3.1.1 Dirac structure

Consider a finite dimensional space F over the field \mathbb{R} and $E \equiv F'$ its dual, i.e. the space of linear operator $\mathbf{e} : F \rightarrow \mathbb{R}$. The elements of F are called flows, while the elements of E are called efforts. Those are port variables and their combination gives the power flowing inside the system. The space $B = F \times E$ is called the bond space of power variables. Therefore the power is defined as $\langle \mathbf{e}, \mathbf{f} \rangle = e(\mathbf{f})$, where $\langle \mathbf{e}, \mathbf{f} \rangle$ is the dual product between \mathbf{f} and \mathbf{e} .

Definition 1 (Dirac Structure [Cou90], Def. 1.1.1)

Given the finite-dimensional space F and its dual E with respect to the inner product $\langle \cdot, \cdot \rangle_{E \times F} : F \times E \rightarrow \mathbb{R}$, consider the symmetric bilinear form:

$$\langle \langle (\mathbf{f}_1, \mathbf{e}_1), (\mathbf{f}_2, \mathbf{e}_2) \rangle \rangle := \langle \mathbf{e}_1, \mathbf{f}_2 \rangle_{E \times F} + \langle \mathbf{e}_2, \mathbf{f}_1 \rangle_{E \times F}, \quad \text{where} \quad \mathbf{f}_i, \mathbf{e}_i \in B, \quad i = 1, 2 \quad (3.1)$$

A Dirac structure on $B := F \times E$ is a subspace $D \subset B$, which is maximally isotropic under $\langle \langle \cdot, \cdot \rangle \rangle$. Equivalently, a Dirac structure on $B := F \times E$ is a subspace $D \subset B$ which equals its orthogonal complement with respect to $\langle \langle \cdot, \cdot \rangle \rangle : D = D^\perp$.

This definition can be extended to consider distributed forces and dissipation [Vil07].

Proposition 1 (Characterization of Dirac structures)

Consider the space of power variables $F \times E$ and let X denote an n -dimensional space, the space of energy variables. Suppose that $F := F_s \times F_e$ and that $E := E_s \times E_e$, with $\dim F_s = \dim E_s = n$ and $\dim F_e = \dim E_e = m$. Moreover, let $\mathbf{J}(\mathbf{x})$ denote a skew-symmetric matrix of dimension n and $\mathbf{B}(\mathbf{x})$ a matrix of dimension $n \times m$. Then, the set

$$D := \left\{ (\mathbf{f}_s, \mathbf{f}_e, \mathbf{e}_s, \mathbf{e}_e) \in F \times E \mid \mathbf{f}_s = \mathbf{J}(\mathbf{x})\mathbf{e}_s + \mathbf{B}(\mathbf{x})\mathbf{f}_e, \mathbf{e}_e = -\mathbf{B}(\mathbf{x})^\top \mathbf{e}_s \right\} \quad (3.2)$$

is a Dirac structure.

It is now possible to make the connection between Dirac structures and pH system explicit.

3.1.2 Finite dimensional port-Hamiltonian systems

Consider the time-invariant dynamical system:

$$\begin{cases} \dot{\mathbf{x}} &= \mathbf{J}(\mathbf{x})\nabla H(\mathbf{x}) + \mathbf{B}(\mathbf{x})\mathbf{u}, \\ \mathbf{y} &= \mathbf{B}(\mathbf{x})^\top \nabla H(\mathbf{x}), \end{cases} \quad (3.3)$$

where $H(\mathbf{x}) : X \subset \mathbb{R}^n \rightarrow \mathbb{R}$, the Hamiltonian, is a real-valued function bounded from below. Such a system is called port-Hamiltonian, as it arises from the Hamiltonian modelling of a physical system and it interacts with the environment through the input \mathbf{u} , included in the formulation. The connection with the concept of Dirac structure is achieved by considering the following port behavior:

$$\begin{aligned} \mathbf{f}_s &= \dot{\mathbf{x}}, & \mathbf{e}_s &= \nabla H(\mathbf{x}), \\ \mathbf{f}_e &= \mathbf{u}, & \mathbf{e}_e &= -\mathbf{y}. \end{aligned} \quad (3.4)$$

With this choice of the port variables, system (3.3) defines, by Proposition 1, a Dirac structure. Dissipation and distributed forces can be included and the corresponding system defines an extended Dirac structure, once the proper port variables have been introduced.

System 3.3 is a pH system in canonical form. Recently, finite dimensional differential algebraic port-Hamiltonian systems (pHDAE) have been introduced both for linear [BMXZ18] and non linear systems [MM19]. This enriched description share all the crucial features of ordinary pHs, but easily account for algebraic constraints, time-dependent transformations and explicit dependence on time in the Hamiltonian. The application of the proposed discretization method lead naturally to pHDAE systems.

3.2 Infinite dimensional setting

Infinite dimensional spaces appears whenever differential operators have to be considered. In this section we first explain what defines a differential operator. Then Stokes-Dirac structures, characterized by a skew-symmetric differential operator, are introduced. Finally distributed port-Hamiltonian systems and their connection to the concept of Stokes-Dirac structure are illustrated.

Before starting we recall how inner products of square integrable function are computed. Let Ω denote a compact subset of \mathbb{R}^d and let $L^2(\Omega, \mathbb{A})$ be the space of square integrable functions over the set \mathbb{A} in Ω , with inner product denoted by $\langle \cdot, \cdot \rangle_{L^2(\Omega, \mathbb{A})}$. The set \mathbb{A} can either denote scalars \mathbb{R} , vectors \mathbb{R}^d , tensors $\mathbb{R}^{d \times d}$ or a Cartesian product of those. For scalars $(a, b) \in L^2(\Omega)$, vectors $(\mathbf{a}, \mathbf{b}) \in L^2(\Omega, \mathbb{R}^d)$ and tensors $(\mathbf{A}, \mathbf{B}) \in L^2(\Omega, \mathbb{R}^{d \times d})$ the L^2 inner

product is given by

$$\langle a, b \rangle_{L^2(\Omega)} = \int_{\Omega} ab \, d\Omega, \quad \langle \mathbf{a}, \mathbf{b} \rangle_{L^2(\Omega, \mathbb{R}^d)} = \int_{\Omega} \mathbf{a} \cdot \mathbf{b} \, d\Omega, \quad \langle \mathbf{A}, \mathbf{B} \rangle_{L^2(\Omega, \mathbb{R}^{d \times d})} = \int_{\Omega} \mathbf{A} : \mathbf{B} \, d\Omega. \quad (3.5)$$

The notation $\mathbf{A} : \mathbf{B} = \sum_{i,j} A_{ij} B_{ij}$ denotes the tensor contraction. Furthermore, the space of square integrable vector-valued functions over the boundary of Ω is indicated by $L^2(\partial\Omega, \mathbb{R}^m)$.

This space is endowed with the inner product

$$\langle \mathbf{a}_{\partial}, \mathbf{b}_{\partial} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} = \int_{\partial\Omega} \mathbf{a}_{\partial} \cdot \mathbf{b}_{\partial} \, dS, \quad \mathbf{a}_{\partial}, \mathbf{b}_{\partial} \in \mathbb{R}^m. \quad (3.6)$$

3.2.1 Linear differential operators

Let Ω denote a compact subset of \mathbb{R}^d representing the spatial domain of the distributed parameter system. Consider two function space F_1, F_2 over the sets \mathbb{A}, \mathbb{B} defined on $\Omega \subset \mathbb{R}^d$ and a map \mathcal{L} relating the two

$$\mathcal{L} : F_1(\Omega, \mathbb{A}) \longrightarrow F_2(\Omega, \mathbb{B}), \quad \mathbf{u} \longrightarrow \mathbf{v}. \quad (3.7)$$

Sets \mathbb{A}, \mathbb{B} can either denote scalars \mathbb{R} , vectors \mathbb{R}^d , tensors $\mathbb{R}^{d \times d}$ or a Cartesian product of those. Given $\mathbf{u} \in F_1$, $\mathbf{v} \in F_2$ The map \mathcal{L} is a linear differential operator if it can be represented by a linear combination of derivatives of \mathbf{u}

$$\mathbf{v} = \mathcal{L}\mathbf{u} \iff \mathbf{v} := \sum_{|\alpha|=0}^n \mathcal{P}_{\alpha} \partial^{\alpha} \mathbf{u}, \quad (3.8)$$

where $\alpha := (\alpha_1, \dots, \alpha_d)$ is a multi-index of order $|\alpha| := \sum_{i=1}^d \alpha_i$ and $\partial^{\alpha} := \partial_{x_1}^{\alpha_1} \dots \partial_{x_d}^{\alpha_d}$ is a differential operator of order $|\alpha|$ resulting from a combination of spatial derivatives. $\mathcal{P}_{\alpha} : \mathbb{A} \rightarrow \mathbb{B}$ is a constant algebraic operator from set \mathbb{A} to \mathbb{B} .

Example 1 (Divergence operator in \mathbb{R}^d)

Given $\mathbf{u} \in C^{\infty}(\Omega, \mathbb{R}^d)$, $v \in C^{\infty}(\Omega)$, where $C^{\infty}(\Omega, \mathbb{R}^d)$, $C^{\infty}(\Omega)$ denotes the set of smooth vector- and scalar-valued function defined on Ω , the divergence operator in Cartesian coordinate is expressed as

$$v = \operatorname{div} \mathbf{u} = \sum_{i=1}^d \mathbf{e}_i \cdot \partial_{x_i} \mathbf{u}, \quad (3.9)$$

where \mathbf{e}_i is the i -th element of the canonical basis in \mathbb{R}^d .

The differential operators employed in this thesis are reported in Appendix A. A very important notion related to a differential operator is the one of formal adjoint.

Definition 2 (Formal Adjoint)

Let $\mathcal{L} = L^2(\Omega, \mathbb{A}) \rightarrow L^2(\Omega, \mathbb{B})$ be a differential operator and $\mathbf{u} \in C_0^\infty(\Omega, \mathbb{A})$, $\mathbf{v}(\Omega, \mathbb{B})$ be smooth variables with compact support on Ω . The formal adjoint of the differential operator \mathcal{L} , denoted by $\mathcal{L}^* = L^2(\Omega, \mathbb{B}) \rightarrow L^2(\Omega, \mathbb{A})$, is defined by the relation

$$\langle \mathcal{L}\mathbf{u}, \mathbf{v} \rangle_{L^2(\Omega, \mathbb{B})} = \langle \mathbf{u}, \mathcal{L}^*\mathbf{v} \rangle_{L^2(\Omega, \mathbb{A})}. \quad (3.10)$$

This definition represent an extension to generic sets \mathbb{A} , \mathbb{B} of Def. 5.80 in [RR04] (reported in Appendix A).

Remark 1 (Differences between adjoint and formal adjoint)

The definition of formal adjoint is such that the integration by parts formula is respected. Contrarily to the adjoint of an operator, the formal adjoint definition does not regard the actual domain of the operator nor the boundary conditions. For example, the differential operators div , grad are unbounded in the L^2 topology. Whenever unbounded operators are considered, it is important to define their domain. To avoid the need of specifying domains, the notion of formal adjoint is used. The formal adjoint respects the integration by parts formula and is defined only for sufficiently smooth functions with compact support. In this sense the formal adjoint of div is $-\text{grad}$, since for smooth functions with compact support, it holds

$$\langle \text{div } \mathbf{y}, x \rangle_{L^2(\Omega, \mathbb{R})} \underbrace{=}_{I.B.P.} - \langle \mathbf{y}, \text{grad } x \rangle_{L^2(\Omega, \mathbb{R}^d)},$$

for $\mathbf{y} \in C_0^\infty(\Omega, \mathbb{R}^d)$, $x \in C_0^\infty(\Omega)$ (I.B.P. stands for integration by parts). The definition of the domain of the operators, that requires the knowledge of the boundary conditions, has not been specified.

For pHs formally skew-adjoint operators (or simply skew-symmetric) plays a fundamental role.

Definition 3 (Formally skew-adjoint operator)

Let $\mathcal{J} : L^2(\Omega, \mathbb{F}) \rightarrow L^2(\Omega, \mathbb{F})$ be a linear differential operator. Notice that the set \mathbb{F} in the domain and co-domain is the same. Then, \mathcal{J} is formally skew-adjoint (or skew-symmetric) if and only if $\mathcal{J} = -\mathcal{J}^*$.

If functions with compact support are considered, i.e. $\mathbf{u}_1, \mathbf{u}_2 \in C_0^\infty(\Omega, \mathbb{F})$ a formally skew-adjoint operators is characterized by the relation

$$\langle \mathcal{J}\mathbf{u}_1, \mathbf{u}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{u}_1, \mathcal{J}\mathbf{u}_2 \rangle_{L^2(\Omega, \mathbb{A})} = 0. \quad (3.11)$$

3.2.2 Constant Stokes-Dirac structures

Constant Stokes-Dirac structures are the infinite-dimensional generalization of constant Dirac structures (i.e. Dirac structures for which the matrices \mathbf{J} , \mathbf{B} in (3.3) are constant). Stokes-

Dirac structure are characterized by the fact that they are equal their orthogonal complement with respect to a bilinear product. So we recall the definition of orthogonal companion for the case of smooth functions.

Definition 4 (Orthogonal complement)

Let $\Omega \subset \mathbb{R}^d$, $d \in \{1, 2, 3\}$ be an open connected set and $C^\infty(\partial\Omega, \mathbb{R}^m)$ the space of smooth functions over its boundary. Consider the space

$$B = C^\infty(\Omega, \mathbb{F}) \times C^\infty(\partial\Omega, \mathbb{R}^m) \times C^\infty(\Omega, \mathbb{F}) \times C^\infty(\partial\Omega, \mathbb{R}^m) \quad (3.12)$$

and the bilinear pairing defined by

$$\begin{aligned} \langle \langle \cdot, \cdot \rangle \rangle : B \times B &\longrightarrow \mathbb{R}, \\ (\mathbf{a}, \mathbf{a}_\partial, \mathbf{b}, \mathbf{b}_\partial) \times (\mathbf{c}, \mathbf{c}_\partial, \mathbf{d}, \mathbf{d}_\partial) &\longrightarrow \langle \mathbf{a}, \mathbf{d} \rangle_{L^2(\Omega, \mathbb{F})} + \langle \mathbf{b}, \mathbf{c} \rangle_{L^2(\Omega, \mathbb{F})} + \\ &\quad \langle \mathbf{a}_\partial, \mathbf{d}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \mathbf{b}_\partial, \mathbf{c}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \quad (3.13)$$

Given a linear subspace $W \subset B$, its orthogonal complement is the set

$$W^\perp = \{\mathbf{v} \in B \mid \langle \langle \mathbf{v}, \mathbf{w} \rangle \rangle = 0, \forall \mathbf{w} \in W\} \quad (3.14)$$

We can now define what a Stokes-Dirac structure is.

Definition 5 (Stokes-Dirac structure)

A subset $D \subset B$, with B defined in (3.12), is a Stokes-Dirac structure iff

$$D = D^\perp, \quad (3.15)$$

where the orthogonal complement has been defined in Eq. (3.14)

For a subset to be a Stokes-Dirac structures a link between flow and effort variables must hold. Consider $\mathbf{f} \in C^\infty(\Omega, \mathbb{F})$ and $\mathbf{e} \in C^\infty(\Omega, \mathbb{F})$ and the following relation between the two

$$\mathbf{f} = \mathcal{J}\mathbf{e}, \quad \mathcal{J} = -\mathcal{J}^*, \quad (3.16)$$

where \mathcal{J} is a formally skew-adjoint operator. A Stokes-Dirac structure requires the specification of boundary variables in order to express a general power conservation property for open physical systems. We make therefore the following assumption, over the existence of appropriate boundary operators.

Assumption 1 (Existence of boundary operators)

Assume that exist two linear boundary operators $\mathcal{B}_\partial, \mathcal{C}_\partial$ such that for $\mathbf{u}_1, \mathbf{u}_2 \in C^\infty(\Omega, \mathbb{F})$ the following integration by parts formula holds

$$\langle \mathcal{J}\mathbf{u}_1, \mathbf{u}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{u}_1, \mathcal{J}\mathbf{u}_2 \rangle_{L^2(\Omega, \mathbb{A})} = \langle \mathcal{B}_\partial\mathbf{u}_1, \mathcal{C}_\partial\mathbf{u}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \mathcal{B}_\partial\mathbf{u}_2, \mathcal{C}_\partial\mathbf{u}_1 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \quad (3.17)$$

This assumption is necessary to appropriately define a Stokes-Dirac structure. Only few particular cases, like the transport equation, do not verify it. We can now characterize generic Stokes-Dirac structure for smooth functions spaces.

Proposition 2 (Characterization of Stokes-Dirac structures)

Let B be defined as in Eq. (3.12) and \mathcal{J} be a formally skew adjoint operator verifying Assumption 1. The set

$$D_{\mathcal{J}} = \{(\mathbf{f}, \mathbf{f}_{\partial}, \mathbf{e}, \mathbf{e}_{\partial}) \in B \mid \mathbf{f} = \mathcal{J}\mathbf{e}, \mathbf{f}_{\partial} = \mathcal{B}_{\partial}\mathbf{e}, \mathbf{e}_{\partial} = -\mathcal{C}_{\partial}\mathbf{e}\} \quad (3.18)$$

is a Stokes-Dirac structure with respect to the bilinear pairing (3.13).

Proof. A Stokes-Dirac is characterized by the fact that $D_{\mathcal{J}} = D_{\mathcal{J}}^{\perp}$. Then one has to show that $D_{\mathcal{J}} \subset D_{\mathcal{J}}^{\perp}$ and $D_{\mathcal{J}}^{\perp} \subset D_{\mathcal{J}}$. Following [LGZM05], the proof is obtained following three steps.

Step 1. To show that $D_{\mathcal{J}} \subset D_{\mathcal{J}}^{\perp}$, take $(\mathbf{f}, \mathbf{f}_{\partial}, \mathbf{e}, \mathbf{e}_{\partial}) \in D_{\mathcal{J}}$. Then

$$\begin{aligned} \langle (\mathbf{f}, \mathbf{f}_{\partial}, \mathbf{e}, \mathbf{e}_{\partial}), (\mathbf{f}, \mathbf{f}_{\partial}, \mathbf{e}, \mathbf{e}_{\partial}) \rangle &= 2 \langle \mathbf{e}, \mathbf{f} \rangle_{L^2(\Omega, \mathbb{F})} + 2 \langle \mathbf{e}_{\partial}, \mathbf{f}_{\partial} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &= 2 \langle \mathbf{e}, \mathcal{J}\mathbf{e} \rangle_{L^2(\Omega, \mathbb{F})} + 2 \langle \mathbf{e}_{\partial}, \mathbf{f}_{\partial} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &\stackrel{\text{Eq. (3.17)}}{=} 2 \langle \mathcal{B}_{\partial}\mathbf{e}, \mathcal{C}_{\partial}\mathbf{e} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + 2 \langle \mathbf{e}_{\partial}, \mathbf{f}_{\partial} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &\stackrel{\text{Eq. (3.18)}}{=} 2 \langle \mathcal{B}_{\partial}\mathbf{e}, \mathcal{C}_{\partial}\mathbf{e} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} - 2 \langle \mathcal{B}_{\partial}\mathbf{e}, \mathcal{C}_{\partial}\mathbf{e} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &= 0. \end{aligned}$$

This implies $D_{\mathcal{J}} \subset D_{\mathcal{J}}^{\perp}$.

Step 2. Take $(\phi, \phi_{\partial}, \epsilon, \epsilon_{\partial}) \in D_{\mathcal{J}}^{\perp}$ and $\mathbf{e}_0 \in C_0^{\infty}(\Omega, \mathbb{F})$. This implies $\mathcal{B}_{\partial}\mathbf{e}_0 = (\mathbf{0}, \mathbf{0})$ and $\mathcal{C}_{\partial}\mathbf{e}_0 = (\mathbf{0}, \mathbf{0})$. Taking $(\mathcal{J}\mathbf{e}_0, \mathbf{0}, \mathbf{e}_0, \mathbf{0}) \in D_{\mathcal{J}}$ then

$$\langle (\phi, \phi_{\partial}, \epsilon, \epsilon_{\partial}), (\mathcal{J}\mathbf{e}_0, \mathbf{0}, \mathbf{e}_0, \mathbf{0}) \rangle = \langle \epsilon, \mathcal{J}\mathbf{e}_0 \rangle_{L^2(\Omega, \mathbb{F})} + \langle \mathbf{e}_0, \phi \rangle_{L^2(\Omega, \mathbb{F})} = 0, \quad \forall \mathbf{e}_0 \in C_0^{\infty}(\Omega, \mathbb{F}).$$

It follows that $\epsilon \in C_0^{\infty}(\Omega, \mathbb{F})$ and $\phi = \mathcal{J}\epsilon$.

Step 3. Take $(\phi, \phi_{\partial}, \epsilon, \epsilon_{\partial}) \in D_{\mathcal{J}}^{\perp}$ and $(\mathbf{f}, \mathbf{f}_{\partial}, \mathbf{e}, \mathbf{e}_{\partial}) \in D_{\mathcal{J}}$. From step 2 and (3.17)

$$\begin{aligned}
0 &= \langle \mathcal{J}e, \epsilon \rangle_{L^2(\Omega, \mathbb{F})} + \langle e, \mathcal{J}\epsilon \rangle_{L^2(\Omega, \mathbb{F})} + \langle e_\partial, \phi_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \epsilon_\partial, f_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
&\stackrel{\text{Eq. (3.17)}}{=} \langle \mathcal{B}_\partial e, \mathcal{C}_\partial \epsilon \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \mathcal{B}_\partial \epsilon, \mathcal{C}_\partial e \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle e_\partial, \phi_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \epsilon_\partial, f_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
&= \langle \mathcal{B}_\partial e, \mathcal{C}_\partial \epsilon \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \mathcal{B}_\partial \epsilon, \mathcal{C}_\partial e \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle -\mathcal{C}_\partial e, \phi_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \epsilon_\partial, \mathcal{B}_\partial e \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
&= \langle \mathcal{B}_\partial e, \mathcal{C}_\partial \epsilon + \epsilon_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} + \langle \mathcal{B}_\partial \epsilon - \phi_\partial, \mathcal{C}_\partial e \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \quad \text{By linearity,} \\
&= \langle e_\partial, \mathcal{C}_\partial \epsilon + \epsilon_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} - \langle \mathcal{B}_\partial \epsilon - \phi_\partial, f_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}.
\end{aligned}$$

Given the fact that e_∂, f_∂ are arbitrary then

$$\phi_\partial = \mathcal{B}_\partial \epsilon, \quad \epsilon_\partial = -\mathcal{C}_\partial \epsilon,$$

400 meaning that $D_{\mathcal{J}}^\perp \subset D_{\mathcal{J}}$. This concludes the proof. \square

401 3.2.3 Distributed port-Hamiltonian system

402 A distributed lossless port-Hamiltonian system is defined by a set of variables that describes
 403 the unknowns, by a formally skew-adjoint differential operator, an energy functional and a
 404 set of boundary inputs and corresponding conjugated outputs. Such a system is described by
 405 the following set of equations, defined on an open connected set $\Omega \subset \mathbb{R}^d$

$$\begin{aligned}
\partial_t \alpha &= \mathcal{J} \delta_\alpha H, & \alpha &\in C^\infty(\Omega, \mathbb{F}), \\
u_\partial &= \mathcal{B}_\partial \delta_\alpha H, & u_\partial &\in \mathbb{R}^m, \\
y_\partial &= \mathcal{C}_\partial \delta_\alpha H, & y_\partial &\in \mathbb{R}^m.
\end{aligned} \tag{3.19}$$

406 The unknowns α are called energy variables in the port-Hamiltonian framework, the formally
 407 skew-adjoint operator \mathcal{J} is named interconnection operator (see Def. 3 for a precise definition
 408 of formal skew adjointness). $\mathcal{B}_\partial, \mathcal{C}_\partial$ are boundary operators, that provide the boundary input
 409 u_∂ and output y_∂ [TW09, Chapter 4]. The functional $H(\alpha) : C^\infty(\Omega, \mathbb{F}) \rightarrow \mathbb{R}$ corresponds to
 410 the Hamiltonian functional and in all the examples considered in this thesis coincide with the
 411 total energy of the system. Notation $\delta_\alpha H$ indicates the variational derivative of H .

Definition 6 (Variational derivative, Def. 4.1 in [Olv93])

Consider a functional $H(\alpha) : C^\infty(\Omega, \mathbb{F}) \rightarrow \mathbb{R}$

$$H(\alpha) = \int_\Omega \mathcal{H}(\alpha) \, d\Omega.$$

Given a variation $\alpha = \bar{\alpha} + \eta \delta \alpha$ the variational derivative $\frac{\delta H}{\delta \alpha}$ is defined as

$$H(\bar{\alpha} + \eta \delta \alpha) = H(\bar{\alpha}) + \eta \langle \delta_\alpha H, \delta \alpha \rangle_{L^2(\Omega, \mathbb{F})} + O(\eta^2).$$

Remark 2

If the integrand does not contain derivative of the argument α then the variational derivative is equal to the partial derivative of the Hamiltonian density \mathcal{H}

$$\frac{\delta H}{\delta \alpha} = \frac{\partial \mathcal{H}}{\partial \alpha}.$$

Remark 3 (Co-energy variables)

The variational derivative of the Hamiltonian defines the co-energy variables $\mathbf{e} := \delta_\alpha H$. These are equivalent to the effort variables of the Stokes-Dirac structure as we will immediately show.

Suppose that operators \mathcal{J} , \mathcal{B}_∂ , \mathcal{C}_∂ in Eq. 3.19 verify Ass. 1. Then, System (3.19) is lossless since the energy rate is given by

$$\begin{aligned} \dot{H} &= \langle \delta_\alpha H, \partial_t \alpha \rangle_{L^2(\Omega, \mathbb{F})}, \\ &\stackrel{\text{Eq. (3.17)}}{=} \langle \mathcal{B}_\partial \delta_\alpha H, \mathcal{C}_\partial \delta_\alpha H \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &= \langle \mathbf{u}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \tag{3.20}$$

The connection between the concept of Stokes-Dirac structure and dpHs becomes clear if the following port behavior is considered

$$\begin{aligned} \mathbf{f} &= \partial_t \alpha, & \mathbf{e} &= \delta_\alpha H, \\ \mathbf{f}_\partial &= \mathbf{u}_\partial, & \mathbf{e}_\partial &= -\mathbf{y}_\partial. \end{aligned} \tag{3.21}$$

By proposition (2) System (3.19) under the port behavior (3.21) defines a Stokes-Dirac structure. No rigorous characterization has been given so far for operators \mathcal{J} , \mathcal{B}_∂ , \mathcal{C}_∂ in system (3.19). A formal characterization of these operators has been given in [LGZM05] for pH of generic order only in one geometrical dimensional. In Chapter 7 the operator \mathcal{J} will be better characterize using an appropriate partition. By applying a general integration by parts formula, the operators \mathcal{B}_∂ , \mathcal{C}_∂ associated to \mathcal{J} can be defined as well. The following examples clarifies this assertion for some known pHs.

3.2.3.1 Wave equation

Given an open bounded connected set $\Omega \subset \mathbb{R}^2$ with Lipschitz continuous boundary $\partial\Omega$, the propagation of sound in air can be described by the following model [TRLGK18]

$$\begin{aligned} \chi_s \partial_t p(\mathbf{x}, t) &= -\operatorname{div} \mathbf{v}, \\ \mu_0 \partial_t \mathbf{v}(\mathbf{x}, t) &= -\operatorname{grad} p, \end{aligned} \tag{3.22}$$

where the scalars χ_s , μ_0 are the constant adiabatic compressibility factor and the steady state mass density respectively. The scalar field $p \in \mathbb{R}$ and vector field $\mathbf{v} \in \mathbb{R}^2$ represents the variation of pressure and velocity from the steady state. The Hamiltonian (total energy) reads

$$H = \frac{1}{2} \int_{\Omega} \left\{ \chi_s p^2 + \mu_0 \|\mathbf{v}\|^2 \right\} d\Omega.$$

To recast (3.22) in pH form the energy variables has to be introduced $\boldsymbol{\alpha} = [\alpha_p, \boldsymbol{\alpha}_v]^\top$

$$\alpha_p := \chi_s p, \quad \boldsymbol{\alpha}_v := \mu_0 \mathbf{v}.$$

The Hamiltonian is rewritten as

$$H = \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\chi_s} \alpha_p^2 + \frac{1}{\mu_0} \|\boldsymbol{\alpha}_v\|^2 \right\} d\Omega.$$

By definition, the co-energy are

$$e_p = \frac{\delta H}{\delta \alpha_p} = \frac{1}{\chi_s} \alpha_p = p, \quad \mathbf{e}_v = \frac{\delta H}{\delta \boldsymbol{\alpha}_v} = \frac{1}{\mu_0} \boldsymbol{\alpha}_v = \mathbf{v}.$$

Equation (3.22) can be recast in port-Hamiltonian form

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_p \\ \boldsymbol{\alpha}_v \end{pmatrix} = - \begin{bmatrix} 0 & \text{div} \\ \text{grad} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_p \\ \mathbf{e}_v \end{pmatrix}.$$

From the energy rate it is possible to identify the boundary variables.

$$\begin{aligned} \dot{H} &= + \int_{\Omega} \{e_p \partial_t \alpha_p + \mathbf{e}_v \cdot \partial_t \boldsymbol{\alpha}_v\} d\Omega, \\ &= - \int_{\Omega} \{e_p \text{div} \mathbf{e}_v + \mathbf{e}_v \cdot \text{grad} e_p\} d\Omega, && \text{Chain rule,} \\ &= - \int_{\Omega} \text{div}(e_p \mathbf{e}_v) d\Omega, && \text{Stokes theorem,} \\ &= - \int_{\partial\Omega} e_p \mathbf{e}_v \cdot \mathbf{n} dS = - \langle e_p, \mathbf{e}_v \cdot \mathbf{n} \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}. \end{aligned}$$

429 The boundary term $\langle e_p, \mathbf{e}_v \cdot \mathbf{n} \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}$ pairs two power variables. One is taken as control
 430 input, the other plays the role of power-conjugated output. The assignment of these roles to
 431 the boundary power variables is referred to as causality of the boundary port [KML18],[Kot19,
 432 Chapter 2]. Under uniform causality assumption, either e_p or \mathbf{e}_v can assume the role of
 433 (distributed) boundary input, but not both. This leads to two possible selections:

- 434 • First case $u_{\partial} = e_p, \quad y_{\partial} = \mathbf{e}_v \cdot \mathbf{n}$.
 435 This imposes the variable $e_p := p$ as boundary input and corresponds to a classical
 436 Dirichlet condition. The boundary operator for this case are given by

$$\mathcal{B}_{\partial} \begin{pmatrix} e_p \\ \mathbf{e}_v \end{pmatrix} = e_p|_{\partial\Omega}, \quad \mathcal{C}_{\partial} \begin{pmatrix} e_p \\ \mathbf{e}_v \end{pmatrix} = \mathbf{e}_v \cdot \mathbf{n}|_{\partial\Omega},$$

437 corresponding to the standard trace and normal trace operators.

- 438 • Second case $u_{\partial} = \mathbf{e}_v \cdot \mathbf{n}, \quad y_{\partial} = e_p$.
 439 This imposes the variable $\mathbf{e}_v \cdot \mathbf{n} := \mathbf{v} \cdot \mathbf{n}$ as boundary input and corresponds to a
 440 Neumann condition. The boundary operators are therefore switched with respect to

the previous case

$$\mathcal{B}_\partial \begin{pmatrix} e_p \\ e_v \end{pmatrix} = e_v \cdot \mathbf{n}|_{\partial\Omega}, \quad \mathcal{C}_\partial \begin{pmatrix} e_p \\ e_v \end{pmatrix} = e_p|_{\partial\Omega}.$$

3.2.3.2 Euler Bernoulli beam

The Euler-Bernoulli beam model consists of one PDE, describing the vertical displacement along the beam length:

$$\rho A(x) \frac{\partial^2 w}{\partial t^2}(x, t) + \frac{\partial^2}{\partial x^2} \left(EI(x) \frac{\partial^2 w}{\partial x^2} \right) = 0, \quad x \in \Omega = \{0, L\}, \quad (3.23)$$

where $w(x, t)$ is the transverse displacement of the beam. The coefficients $\rho(x)$, $A(x)$, $E(x)$ and $I(x)$ are the mass density, cross section, Young's modulus of elasticity and the moment of inertia of a cross section. The energy variables are then chosen as follows:

$$\alpha_w = \rho A(x) \frac{\partial w}{\partial t}(x, t), \quad \text{Linear Momentum}, \quad \alpha_\kappa = \frac{\partial^2 w}{\partial x^2}(x, t), \quad \text{Curvature}. \quad (3.24)$$

Those variables are collected in the vector $\alpha = (\alpha_w, \alpha_\kappa)^T$, so that the Hamiltonian can be written as a quadratic functional in the energy variables:

$$H = \frac{1}{2} \int_\Omega \left\{ \frac{1}{\rho A} \alpha_w^2 + EI \alpha_\kappa^2 \right\} d\Omega \quad (3.25)$$

The co-energy variables are found by computing the variational derivative of the Hamiltonian:

$$\begin{aligned} e_w &:= \frac{\delta H}{\delta \alpha_w} = \frac{\partial w}{\partial t}(x, t), & \text{Vertical velocity,} \\ e_\kappa &:= \frac{\delta H}{\delta \alpha_\kappa} = EI(x) \frac{\partial^2 w}{\partial x^2}(x, t), & \text{Flexural momentum.} \end{aligned} \quad (3.26)$$

The underlying interconnection structure is then found to be:

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \alpha_\kappa \end{pmatrix} = \begin{bmatrix} 0 & -\partial_{xx} \\ \partial_{xx} & 0 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}. \quad (3.27)$$

The power flow gives access to the boundary variables:

$$\begin{aligned} \dot{H} &= \int_\Omega \{e_w \partial_t \alpha_w + e_\kappa \partial_t \alpha_\kappa\} d\Omega, \\ &= \int_\Omega \{-e_w \partial_{xx} e_\kappa + e_\kappa \partial_{xx} e_w\} d\Omega, & \text{Integration by parts,} \\ &= \int_{\partial\Omega} \{-e_w \partial_x e_\kappa + e_\kappa \partial_x e_w\} ds = \langle -e_w|_{\partial\Omega}, \partial_x e_\kappa|_{\partial\Omega} \rangle_{\mathbb{R}^4} + \langle e_\kappa|_{\partial\Omega}, \partial_x e_w|_{\partial\Omega} \rangle_{\mathbb{R}^4} \end{aligned} \quad (3.28)$$

Since the system is of differential order two, two pairing appears, giving rise to four combination of uniform boundary causality

- First case $u_{\partial,1} = e_w$, $u_{\partial,2} = \partial_x e_w$, $y_{\partial,1} = -\partial_x e_\kappa$, $y_{\partial,2} = e_\kappa$.
This imposes the vertical $e_w := \partial_t w$ and angular velocity $\partial_x e_w := \partial_{xt} w$ as boundary inputs

$$\mathcal{B}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} e_w(L) \\ -e_w(0) \\ \partial_x e_w(L) \\ -\partial_x e_w(0) \end{pmatrix} \in \mathbb{R}^4 \quad \mathcal{C}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} -\partial_x e_\kappa(L) \\ \partial_x e_\kappa(0) \\ e_\kappa(L) \\ -e_\kappa(0) \end{pmatrix} \in \mathbb{R}^4 \quad (3.29)$$

If the inputs are null a clamped boundary condition is obtained.

- Second case $u_{\partial,1} = e_w$, $u_{\partial,2} = e_\kappa$, $y_{\partial,1} = -\partial_x e_\kappa$, $y_{\partial,2} = \partial_x e_w$.
This imposes the vertical velocity and flexural momentum $e_\kappa := EI \partial_{xx} w$ as boundary inputs

$$\mathcal{B}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} e_w(L) \\ -e_w(0) \\ e_\kappa(L) \\ -e_\kappa(0) \end{pmatrix} \in \mathbb{R}^4 \quad \mathcal{C}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} -\partial_x e_\kappa(L) \\ \partial_x e_\kappa(0) \\ \partial_x e_w(L) \\ -\partial_x e_w(0) \end{pmatrix} \in \mathbb{R}^4 \quad (3.30)$$

Zero inputs lead to a simply supported condition.

- Third case $u_{\partial,1} = -\partial_x e_\kappa$, $u_{\partial,2} = e_\kappa$, $y_{\partial,1} = e_w$, $y_{\partial,2} = \partial_x e_w$.
This imposes the shear force $\partial_x e_\kappa := \partial_x (EI \partial_{xx} w)$ and flexural momentum as boundary inputs

$$\mathcal{B}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} -\partial_x e_\kappa(L) \\ \partial_x e_\kappa(0) \\ e_\kappa(L) \\ -e_\kappa(0) \end{pmatrix} \in \mathbb{R}^4 \quad \mathcal{C}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} e_w(L) \\ -e_w(0) \\ \partial_x e_w(L) \\ -\partial_x e_w(0) \end{pmatrix} \in \mathbb{R}^4 \quad (3.31)$$

Null inputs correspond to a free condition.

- Fourth case $u_{\partial,1} = -\partial_x e_\kappa$, $u_{\partial,2} = \partial_x e_w$, $y_{\partial,1} = e_w$, $y_{\partial,2} = e_\kappa$.
This imposes the shear force and angular velocity as boundary inputs

$$\mathcal{B}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} -\partial_x e_\kappa(L) \\ \partial_x e_\kappa(0) \\ \partial_x e_w(L) \\ -\partial_x e_w(0) \end{pmatrix} \in \mathbb{R}^4 \quad \mathcal{C}_\partial \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{pmatrix} e_w(L) \\ -e_w(0) \\ e_\kappa(L) \\ -e_\kappa(0) \end{pmatrix} \in \mathbb{R}^4 \quad (3.32)$$

3.2.3.3 2D shallow water equations

This formulation may be found in [CR16, Section 6.2]. This model describes a thin fluid layer of constant density in hydrostatic balance, like the propagation of a tsunami wave far from

shore. Consider an open bounded connected set $\Omega \subset \mathbb{R}^2$ and a constant bed profile. The mass conservation implies

$$\frac{\partial h}{\partial t} + \operatorname{div}(h\mathbf{v}) = 0,$$

where $h(x, y, t) \in \mathbb{R}$ is a scalar field representing the fluid height, $\mathbf{v}(x, y, t) \in \mathbb{R}^2$ is the fluid velocity field. The conservation of linear momentum reads

$$\frac{\partial \rho \mathbf{v}}{\partial t} + \rho(\mathbf{v} \cdot \nabla) \mathbf{v} + \nabla(\rho g h) = 0,$$

where ρ is the mass density and g the gravitational acceleration constant. Using the identity

$$(\mathbf{v} \cdot \nabla) \mathbf{v} = \frac{1}{2} \nabla(\|\mathbf{v}\|^2) + (\nabla \times \mathbf{v}) \times \mathbf{v},$$

where $\nabla \times$ is the rotational of \mathbf{v} (also denoted $\operatorname{curl} \mathbf{v}$), the momentum is rearranged as follows

$$\frac{\partial \rho \mathbf{v}}{\partial t} = -\nabla \left(\frac{1}{2} \rho \|\mathbf{v}\|^2 + \rho g h \right) - \rho(\nabla \times \mathbf{v}) \times \mathbf{v}.$$

The last term on the right-hand side can be rewritten

$$\rho(\nabla \times \mathbf{v}) \times \mathbf{v} = \begin{bmatrix} 0 & -\rho\omega \\ \rho\omega & 0 \end{bmatrix} \mathbf{v},$$

with $\omega = \partial_x v_y - \partial_y v_x$ the local vorticity term. To derive a suitable pH formulation, the total energy, made up of kinetic and potential contribution, has to be invoked

$$H = \frac{1}{2} \int_{\Omega} \left\{ \rho h \|\mathbf{v}\|^2 + \rho g h^2 \right\} d\Omega.$$

471 As energy variable the fluid height and the linear momentum are chosen

$$\alpha_h = h, \quad \boldsymbol{\alpha}_v = \rho \mathbf{v}. \quad (3.33)$$

472 The Hamiltonian is a non separable functional of the energy variables

$$H(\alpha_h, \boldsymbol{\alpha}_v) = \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\rho} \alpha_h \|\boldsymbol{\alpha}_v\|^2 + \rho g \alpha_h^2 \right\} d\Omega. \quad (3.34)$$

473 The co-energy variables are given by

$$e_h := \frac{\delta H}{\delta \alpha_h} = \frac{1}{2\rho} \|\boldsymbol{\alpha}_v\|^2 + \rho g \alpha_h, \quad e_v := \frac{\delta H}{\delta \boldsymbol{\alpha}_v} = \frac{1}{\rho} \alpha_h \boldsymbol{\alpha}_v. \quad (3.35)$$

474 The mass and momentum conservation are then rewritten as follows

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_h \\ \boldsymbol{\alpha}_v \end{pmatrix} = \begin{bmatrix} 0 & -\operatorname{div} \\ -\operatorname{grad} & \boldsymbol{\mathcal{G}} \end{bmatrix} \begin{pmatrix} e_h \\ e_v \end{pmatrix}, \quad (3.36)$$

The gyroscopic skew-symmetric term \mathcal{G} introduces a non-linearity as it depends on the energy variables

$$\mathcal{G}(\alpha_h, \alpha_v) = \frac{\omega}{\alpha_h} \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}, \quad \omega = \partial_x \alpha_{v,y} - \partial_y \alpha_{v,x}.$$

Despite the non-standard formulation, the energy rate provides anyway the boundary variables

$$\begin{aligned} \dot{H} &= + \int_{\Omega} \{e_h \partial_t \alpha_h + \mathbf{e}_v \cdot \partial_t \alpha_v\} \, d\Omega, \\ &= - \int_{\Omega} \{e_h \operatorname{div} \mathbf{e}_v + \mathbf{e}_v \cdot (\operatorname{grad} e_h - \mathcal{G} \mathbf{e}_v)\} \, d\Omega, && \text{skew-symmetry of } \mathcal{G}, \\ &= - \int_{\Omega} \{e_h \operatorname{div} \mathbf{e}_v + \mathbf{e}_v \cdot \operatorname{grad} e_h\} \, d\Omega, && \text{Chain rule,} \\ &= - \int_{\Omega} \operatorname{div}(e_h \mathbf{e}_v) \, d\Omega, && \text{Stokes theorem,} \\ &= - \int_{\partial\Omega} e_h \mathbf{e}_v \cdot \mathbf{n} \, dS = - \langle e_h, \mathbf{e}_v \cdot \mathbf{n} \rangle_{\partial\Omega}. \end{aligned} \tag{3.37}$$

Again two possible cases of uniform boundary causality arise:

- First case $u_{\partial} = e_h$, $y_{\partial} = \mathbf{e}_v \cdot \mathbf{n}$.
This imposes the variable $e_h := h$ as boundary input and corresponds to a given water level for a fluid boundary.
- Second case $u_{\partial} = \mathbf{e}_v \cdot \mathbf{n}$, $y_{\partial} = e_p$.
This imposes the variable $\mathbf{e}_v \cdot \mathbf{n} := h\mathbf{v} \cdot \mathbf{n}$ as boundary input and corresponds to a given volumetric flow rate.

3.3 Conclusion

In this chapter, the main mathematical tools needed to understand infinite-dimensional pHs were recalled. A general characterization of the underlying operators behind a boundary control pH system is still an open topic. In Chapter 7, these operators are characterized, in connection to the discretization method developed.

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Part II

490

Port-Hamiltonian elasticity and thermoelasticity

491

Elasticity in port-Hamiltonian form

I try not to break the rules but merely to test their elasticity.

Bill Veeck

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Continuum mechanics is the mathematical description of how materials behave kinematically under external excitations. In this framework, the microscopic structure of a material body is neglected and a macroscopic viewpoint, that describes the body as a continuum, is adopted. This leads to a PDE based model. In this chapter, the general linear elastodynamics problem is recalled. A suitable port-Hamiltonian formulation is then derived.

4.1 Continuum mechanics

In this section, the main concepts behind a deformable continuum are briefly recalled following [Lee12]. For a detailed discussion on this topic, the reader may consult [Abe12, LPKL12].

4.1.1 Non linear formulation of elasticity

The bounded region of \mathbb{R}^d , $d \in \{2, 3\}$ occupied by a solid is called configuration. The reference configuration Ω is the domain that a body occupies at the initial state. To describe how the

body deforms in time the deformation map $\Phi : \Omega \times [0, T_f] \rightarrow \Omega' \subset \mathbb{R}^d$ is introduced. This map is differentiable and orientation preserving, and the image of Ω under $\Phi(\cdot, t) \forall t \in [0, T_f]$ is called the deformed configuration Ω_t . Given a specific point in the reference frame its image is denoted by $\mathbf{y} = \Phi(\mathbf{x}, t)$. The gradient of the deformation map is called the deformation gradient $\mathbf{F} := \nabla_{\mathbf{x}} \Phi = \frac{\partial \mathbf{y}}{\partial \mathbf{x}}$. A rigid deformation maps a point $\mathbf{x} \in \Omega \rightarrow \mathbf{A}(t)\mathbf{x} + \mathbf{b}(t)$, where $\mathbf{A}(t)$ is an orthogonal matrix and $\mathbf{b}(t) \in \mathbb{R}^d$ a vector. A differentiable deformation map Φ is a rigid deformation iff $\mathbf{F}^\top \mathbf{F} - \mathbf{I} = 0$, where \mathbf{I} is the identity in $\mathbb{R}^{d \times d}$ (for the proof see [Cia88], page 44). For this reason, a suitable measure of the deformation is the Green-St.Venant strain tensor $\frac{1}{2}(\mathbf{F}^\top \mathbf{F} - \mathbf{I})$.

A quantity of interest is the displacement $\mathbf{u} : \Omega \times [0, T_f] \rightarrow \mathbb{R}^d$ with respect to the reference configuration. It is defined as $\mathbf{u}(\mathbf{x}, t) = \Phi(\mathbf{x}, t) - \mathbf{x}$. The gradient of the displacement verifies $\nabla_{\mathbf{x}} \mathbf{u} = \mathbf{F} - \mathbf{I}$. The strain tensor can now be written in terms of the displacement

$$\begin{aligned} \frac{1}{2}(\mathbf{F}^\top \mathbf{F} - \mathbf{I}) &= \frac{1}{2} \left[(\nabla_{\mathbf{x}} \mathbf{u} + \mathbf{I})^\top (\nabla_{\mathbf{x}} \mathbf{u} + \mathbf{I}) - \mathbf{I} \right] \\ &= \frac{1}{2} \left[\nabla_{\mathbf{x}} \mathbf{u} + (\nabla_{\mathbf{x}} \mathbf{u})^\top + (\nabla_{\mathbf{x}} \mathbf{u})^\top (\nabla_{\mathbf{x}} \mathbf{u}) \right], \end{aligned}$$

or in components

$$\frac{1}{2}(F_{ik}^\top F_{kj} - I_{ij}) = \frac{1}{2} \left(\frac{\partial u_i}{\partial x_j} + \frac{\partial u_j}{\partial x_i} + \frac{\partial u_i}{\partial x_j} \frac{\partial u_j}{\partial x_i} \right).$$

To state the balance laws the actual deformed configuration is considered. The linear and angular momenta in a subdomain $\omega_t \subset \Omega_t$ are computed as

$$\int_{\omega_t} \rho \mathbf{v} \, d\omega_t, \quad \text{and} \quad \int_{\omega_t} \rho \mathbf{y} \times \mathbf{v} \, d\omega_t,$$

where ρ is the mass density and the velocity $\mathbf{v} = \frac{D\mathbf{u}}{Dt}(\mathbf{y}, t) = \frac{\partial \mathbf{u}}{\partial t}(\mathbf{x}, t)$ is the material time derivative of the displacement (see [Abe12, Chapter 1]). Let $\omega_{t,1}, \omega_{t,2}$ be two subregions in a deformed continuum Ω_t with contacting surface S_{12} . There is a force acting on this surface for a continuum that is called stress vector or traction. If \mathbf{n} is the outward normal at \mathbf{y} on S_{12} with respect to $\omega_{t,1}$, then the surface force that $\omega_{t,1}$ exerts on $\omega_{t,2}$ is denoted by $\mathbf{t}(\mathbf{y}, \mathbf{n}) \in \mathbb{R}^d$. By the Newton third law, the surface force that $\omega_{t,2}$ applies on $\omega_{t,1}$ is given by $\mathbf{t}(\mathbf{y}, -\mathbf{n}) = -\mathbf{t}(\mathbf{y}, \mathbf{n})$. It is assumed that the linear and angular momentum balances hold for any subregion $\omega_t \in \Omega_t$

$$\begin{aligned} \frac{d}{dt} \int_{\omega_t} \rho \mathbf{v} \, d\omega_t &= \int_{\partial \omega_t} \mathbf{t}(\mathbf{y}, \mathbf{n}) \, dS + \int_{\omega_t} \mathbf{f} \, d\omega_t, \\ \frac{d}{dt} \int_{\omega_t} \rho \mathbf{y} \times \mathbf{v} \, d\omega_t &= \int_{\partial \omega_t} \mathbf{y} \times \mathbf{t}(\mathbf{y}, \mathbf{n}) \, dS + \int_{\omega_t} \mathbf{y} \times \mathbf{f} \, d\omega_t, \end{aligned}$$

518 where $\partial \omega_t$ stands for the boundary surface of the subdomain ω_t , \mathbf{n} is the outward normal to
 519 the surface $\partial \omega_t$ and \mathbf{f} represents an exterior body force. The following theorem characterizes
 520 the stress vector (see [Cia88, Chapter 2]):

Theorem 1 (Cauchy's theorem)

If the linear and angular momenta balances hold, then there exists a matrix-valued function Σ from Ω_t to \mathbb{S} such that $\mathbf{t}(\mathbf{y}, \mathbf{n}) = \Sigma(\mathbf{y})\mathbf{n}$, $\forall \mathbf{y} \in \Omega_t$ where the right-hand side is the matrix-vector multiplication.

The set $\mathbb{S} = \mathbb{R}_{\text{sym}}^{d \times d}$ denotes the field of symmetric matrices in $\mathbb{R}^{d \times d}$. The symmetry of the stress tensor Σ is due to the balance of angular momentum. The divergence theorem can then be applied

$$\int_{\partial\omega_t} \Sigma \mathbf{n} \, dS = \int_{\omega_t} \nabla_{\mathbf{y}} \cdot \Sigma \, d\omega_t,$$

where $\nabla_{\mathbf{y}} \cdot$ is the tensor divergence with respect to the deformed configuration, $\nabla_{\mathbf{y}} \cdot \Sigma = \sum_{i=1}^d \frac{\partial \Sigma_{ij}}{\partial y_i}$. Because the considered subregion ω_t is arbitrary, using the linear balance momentum and the conservation of mass, the following PDE is found

$$\rho \frac{D\mathbf{v}}{Dt} - \nabla_{\mathbf{y}} \cdot \Sigma = \mathbf{f}, \quad \mathbf{y} \in \Omega_t.$$

This equation is written with respect to the deformed configuration Ω_t . For a detailed derivation of this equation the reader may consult [Abe12, Chapter 4]. To obtain a closed formulation, the constitutive law, namely the link between the stress tensor Σ and the strain tensor $\frac{1}{2}(\mathbf{F}^\top \mathbf{F} - \mathbf{I})$, has to be introduced. In the next section such relation will be discussed for the case of linear elasticity.

4.1.2 The linear elastodynamics problem

Whenever deformations are small, $\|\nabla_x \mathbf{u}\| \ll 1$, then the reference and deformed configurations are almost indistinguishable $\mathbf{y} = \mathbf{x} + \mathbf{u} = \mathbf{x} + O(\nabla_x \mathbf{u}) \approx \mathbf{x}$. This allows writing the linear momentum balance in the reference configuration

$$\rho \frac{\partial \mathbf{v}}{\partial t}(\mathbf{x}, t) - \text{Div } \Sigma(\mathbf{x}, t) = \mathbf{f}, \quad \mathbf{x} \in \Omega.$$

The material derivative simplifies to a partial one. The operator Div is the divergence of a tensor field with respect to the reference configuration (see Appendix A for a description of the differential operators)

$$\text{Div } \Sigma(\mathbf{x}, t) = \nabla_x \cdot \Sigma(\mathbf{x}, t) = \left(\sum_{i=1}^d \frac{\partial \Sigma_{ij}}{\partial x_i} \right)_{1 \leq j \leq d}.$$

Furthermore, the non-linear terms in the Green-St. Venant strain tensor can be dropped

$$\frac{1}{2}(\mathbf{F}^\top \mathbf{F} - \mathbf{I}) = \frac{1}{2} \left[\nabla_x \mathbf{u} + (\nabla_x \mathbf{u})^\top + (\nabla_x \mathbf{u})^\top (\nabla_x \mathbf{u}) \right] \approx \frac{1}{2} \left[\nabla_x \mathbf{u} + (\nabla_x \mathbf{u})^\top \right].$$

531 The linearized strain tensor (also called infinitesimal strain tensor) is the symmetric gradient
 532 of the displacement

$$\boldsymbol{\varepsilon} := \text{Grad } \mathbf{u}, \quad \text{where} \quad \text{Grad } \mathbf{u} = \frac{1}{2} \left[\nabla_x \mathbf{u} + (\nabla_x \mathbf{u})^\top \right]. \quad (4.1)$$

To obtain a closed system of equations, it is now necessary to characterize the relation between stress and strain. This relation is normally called *constitutive law*. In the following, the particular case of elastic materials is considered. These materials are able to return back to their original size and shapes after forces are removed. For this class of materials, the stress tensor is solely determined from the deformed configuration at a given time (Hooke's law)

$$\boldsymbol{\Sigma}(\mathbf{x}) = \boldsymbol{\mathcal{D}}(\mathbf{x}) \boldsymbol{\varepsilon}(\mathbf{u}(\mathbf{x})).$$

The *stiffness tensor* or *elasticity tensor* $\boldsymbol{\mathcal{D}} : \mathbb{S} \rightarrow \mathbb{S}$ is a rank 4 tensor that is symmetric positive definite and uniformly bounded above and below. Because of symmetry, its components satisfy

$$\mathcal{D}_{ijkl} = \mathcal{D}_{jikl} = \mathcal{D}_{klij}.$$

533 From the uniform boundedness of $\boldsymbol{\mathcal{D}}$, the map $\boldsymbol{\mathcal{D}} : L^2(\Omega, \mathbb{S}) \rightarrow L^2(\Omega, \mathbb{S})$ is a symmetric positive
 534 definite bounded linear operator ($L^2(\Omega, \mathbb{S})$ is the space of square integrable symmetric tensor-
 535 valued functions). The compliance tensor $\boldsymbol{\mathcal{C}}$ is defined by $\boldsymbol{\mathcal{C}} = \boldsymbol{\mathcal{D}}^{-1}$. Thus $\boldsymbol{\mathcal{C}} : \mathbb{S} \rightarrow \mathbb{S}$ is as
 536 well symmetric positive definite and uniformly bounded above and below. An isotropic elastic
 537 medium has the same kinematic properties in any direction and at each point. If an elastic
 538 medium is isotropic, then the stiffness and compliance tensors assume the form

$$\boldsymbol{\mathcal{D}}(\cdot) = 2\mu(\cdot) \mathbf{I} + \lambda \text{Tr}(\cdot) \mathbf{I}, \quad \boldsymbol{\mathcal{C}}(\cdot) = \frac{1}{2\mu} \left[(\cdot) - \frac{\lambda}{2\mu + d\lambda} \text{Tr}(\cdot) \mathbf{I} \right], \quad d = \{2, 3\}, \quad (4.2)$$

539 where Tr is the trace operator and the positive scalar functions μ, λ , defined on Ω , are called
 540 the Lamé coefficients. In engineering applications it is easier to compute experimentally two
 541 other parameters: the Young modulus E and Poisson's ratio ν . Those are expressed in terms
 542 of the Lamé coefficients as

$$\nu = \frac{\lambda}{2(\lambda + \mu)}, \quad E = \frac{\mu(3\lambda + 2\mu)}{\lambda + \mu}, \quad (4.3)$$

543 and conversely

$$\lambda = \frac{E\nu}{(1 + \nu)(1 - 2\nu)}, \quad \mu = \frac{E}{2(1 + \nu)}. \quad (4.4)$$

The stiffness and compliant tensor are expressed as

$$\boldsymbol{\mathcal{D}}(\cdot) = \frac{E}{1 + \nu} \left[(\cdot) + \frac{\nu}{1 - 2\nu} \text{Tr}(\cdot) \mathbf{I} \right], \quad (4.5)$$

$$\boldsymbol{\mathcal{C}}(\cdot) = \frac{1 + \nu}{E} \left[(\cdot) - \frac{\nu}{1 + \nu(d - 2)} \text{Tr}(\cdot) \mathbf{I} \right]. \quad (4.6)$$

The linear elastodynamics problem is formulated through a vector-valued PDE

$$\rho \frac{\partial^2 \mathbf{u}}{\partial t^2} - \text{Div}(\mathcal{D} \text{Grad } \mathbf{u}) = \mathbf{f}. \quad (4.7)$$

The classical elastodynamics problem is expressed considering the displacement \mathbf{u} as the unknown. This PDE goes together with appropriate boundary conditions that will be specified in 4.2.

4.2 Port-Hamiltonian formulation of linear elasticity

In this section a port-Hamiltonian formulation for elasticity is deduced from the classical elastodynamics problem. It must be highlighted that already in the seventies a purely hyperbolic formulation for elasticity was detailed [HM78]. The missing point is the clear connection with the theory of Hamiltonian PDEs. An Hamiltonian formulation can be found in [Gri15, Chapter 16], but without any connection to the concept of Stokes-Dirac structure induced by the underlying geometry.

4.2.1 Energy and co-energy variables

Consider an open connected set $\Omega \subset \mathbb{R}^d$, $d \in \{2, 3\}$. The displacement within a deformable continuum is given by Eq. (4.7).

$$\rho \frac{\partial^2 \mathbf{u}}{\partial t^2} - \text{Div}(\mathcal{D} \text{Grad } \mathbf{u}) = 0, \quad \mathbf{x} \in \Omega. \quad (4.8)$$

The contribution of the body force \mathbf{f} has been removed for ease of presentation. To derive a pH formulation, the total energy, that includes the kinetic and deformation energy, is needed

$$H = \frac{1}{2} \int_{\Omega} \left\{ \rho \|\partial_t \mathbf{u}\|^2 + \boldsymbol{\Sigma} : \boldsymbol{\varepsilon} \right\} d\Omega. \quad (4.9)$$

The notation $\mathbf{A} : \mathbf{B} = \text{Tr}(\mathbf{A}^\top \mathbf{B}) = \sum_{i,j} A_{ij} B_{ij}$ denotes the tensor contraction. Recall that $\boldsymbol{\varepsilon} = \text{Grad } \mathbf{u}$ and $\boldsymbol{\Sigma} = \mathcal{D} \boldsymbol{\varepsilon}$. The energy variables are then the linear momentum and the deformation field

$$\boldsymbol{\alpha}_v = \rho \mathbf{v}, \quad \mathbf{A}_\varepsilon = \boldsymbol{\varepsilon},$$

where $\mathbf{v} := \partial_t \mathbf{u}$. The Hamiltonian can be rewritten as a quadratic functional in the energy variables

$$H = \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\rho} \boldsymbol{\alpha}_v^2 + (\mathcal{D} \mathbf{A}_\varepsilon) : \mathbf{A}_\varepsilon \right\} d\Omega. \quad (4.10)$$

The co-energy variables are given by

$$\mathbf{e}_v := \frac{\delta H}{\delta \boldsymbol{\alpha}_v} = \mathbf{v}, \quad \mathbf{E}_\varepsilon := \frac{\delta H}{\delta \mathbf{A}_\varepsilon} = \boldsymbol{\Sigma}. \quad (4.11)$$

The tensor-valued co-energy \mathbf{E}_ε is obtained by taking the variational derivative with respect to a tensor.

Proposition 3

The variational derivative of the Hamiltonian with respect to the strain tensor is the stress tensor $\delta_{\mathbf{A}_\varepsilon} H = \boldsymbol{\Sigma}$.

Proof. Let $\mathbb{S} : \mathbb{R}_{\text{sym}}^{d \times d}$ be the space of symmetric tensor and $L^2(\Omega, \mathbb{S})$ the space of the square integrable symmetric tensors endowed with the tensor contraction as inner product

$$\langle \mathbf{A}, \mathbf{B} \rangle_{L^2(\Omega, \mathbb{S})} = \int_{\Omega} \mathbf{A} : \mathbf{B} \, d\Omega. \quad (4.12)$$

The contribution due to the deformation part in Hamiltonian is given by:

$$H_{\text{def}}(\mathbf{A}_\varepsilon) = \frac{1}{2} \int_{\Omega} (\mathcal{D} \mathbf{A}_\varepsilon) : \mathbf{A}_\varepsilon \, d\Omega.$$

A variation $\Delta \mathbf{A}_\varepsilon$ of the strain tensor with respect to a given value $\bar{\mathbf{A}}_\varepsilon$ leads to:

$$\begin{aligned} H_{\text{def}}(\bar{\mathbf{A}}_\varepsilon + \eta \Delta \mathbf{A}_\varepsilon) &= + \frac{1}{2} \int_{\Omega} (\mathcal{D} \bar{\mathbf{A}}_\varepsilon) : \bar{\mathbf{A}}_\varepsilon \, d\Omega \\ &+ \eta \frac{1}{2} \int_{\Omega} \left\{ (\mathcal{D} \bar{\mathbf{A}}_\varepsilon) : \Delta \mathbf{A}_\varepsilon + (\mathcal{D} \Delta \mathbf{A}_\varepsilon) : \bar{\mathbf{A}}_\varepsilon \right\} \, d\Omega + O(\eta^2). \end{aligned}$$

The term $(\mathcal{D} \Delta \mathbf{A}_\varepsilon) : \bar{\mathbf{A}}_\varepsilon$ can be further rearranged using the symmetry of \mathcal{D} and the commutativity of the tensor contraction

$$(\mathcal{D} \Delta \mathbf{A}_\varepsilon) : \bar{\mathbf{A}}_\varepsilon = (\mathcal{D} \bar{\mathbf{A}}_\varepsilon) : \Delta \mathbf{A}_\varepsilon,$$

so that

$$H_{\text{def}}(\bar{\mathbf{A}}_\varepsilon + \eta \Delta \mathbf{A}_\varepsilon) = \frac{1}{2} \int_{\Omega} (\mathcal{D} \bar{\mathbf{A}}_\varepsilon) : \bar{\mathbf{A}}_\varepsilon \, d\Omega + \eta \int_{\Omega} (\mathcal{D} \bar{\mathbf{A}}_\varepsilon) : \Delta \mathbf{A}_\varepsilon \, d\Omega + O(\eta^2).$$

By definition of variational derivative it can be written:

$$H_{\text{def}}(\bar{\mathbf{A}}_\varepsilon + \eta \Delta \mathbf{A}_\varepsilon) = H_{\text{def}}(\bar{\mathbf{A}}_\varepsilon) + \eta \left\langle \frac{\delta H}{\delta \mathbf{A}_\varepsilon}, \Delta \mathbf{A}_\varepsilon \right\rangle_{L^2(\Omega, \mathbb{S})} + O(\eta^2),$$

Then, by identification

$$\frac{\delta H_{\text{def}}}{\delta \mathbf{A}_\varepsilon} = \mathcal{D} \bar{\mathbf{A}}_\varepsilon = \boldsymbol{\Sigma}.$$

Since the Hamiltonian is separable then $\delta_{\mathbf{A}_\varepsilon} H_{\text{def}} = \delta_{\mathbf{A}_\varepsilon} H$, leading to the final result. \square

4.2.2 Final system and associated Stokes-Dirac structure

It is now possible to state the final pH form

$$\frac{\partial}{\partial t} \begin{pmatrix} \boldsymbol{\alpha}_v \\ \mathbf{A}_\varepsilon \end{pmatrix} = \begin{bmatrix} \mathbf{0} & \text{Div} \\ \text{Grad} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix}. \quad (4.13)$$

The first equation of the system is the conservation of linear momentum. The second represents a compatibility condition

$$\begin{aligned} \partial_t \mathbf{A}_\varepsilon &= \text{Grad}(\mathbf{e}_v), \\ \partial_t \boldsymbol{\varepsilon} &= \text{Grad}(\mathbf{v}), \\ \partial_t \text{Grad } \mathbf{u} &= \text{Grad}(\partial_t \mathbf{u}). \end{aligned} \quad (4.14)$$

Assuming that $\mathbf{u} \in C^2$, higher order derivatives commute (Clairaut's theorem). Hence, the equation is verified. The following theorem ensures the differential operator is formally skew-adjoint (one can also find this result in the recent article [PZ20, Lemma 3.3], available as arXiv preprint).

Theorem 2

The formal adjoint of the tensor divergence Div is $-\text{Grad}$, the opposite of the symmetric gradient.

Proof. We denote by $\mathbb{V} = \mathbb{R}^d$ the space of vector field in \mathbb{R}^d and by $\mathbb{S} = \mathbb{R}^{d \times d}$ the space of symmetric tensor field in $\mathbb{R}^{d \times d}$. Let us consider the Hilbert space of the square integrable symmetric tensors $L^2(\Omega, \mathbb{S})$ with scalar product defined in (4.12). Moreover consider the Hilbert space of the square integrable vector function $L^2(\Omega, \mathbb{V})$, endowed with the usual scalar product

$$\langle \mathbf{a}, \mathbf{b} \rangle_{L^2(\Omega, \mathbb{V})} = \int_{\Omega} \mathbf{a} \cdot \mathbf{b} \, d\Omega.$$

Let us consider the tensor divergence operator defined as:

$$\begin{aligned} \text{Div} : L^2(\Omega, \mathbb{S}) &\rightarrow L^2(\Omega, \mathbb{V}), \\ \boldsymbol{\Psi} &\rightarrow \text{Div } \boldsymbol{\Psi} = \boldsymbol{\psi}, \end{aligned} \quad \text{with } \psi_j = \text{div}(\Psi_{ij}) = \sum_{i=1}^d \frac{\partial \Psi_{ij}}{\partial x_i}.$$

We try to identify Div^*

$$\begin{aligned} \text{Div}^* : L^2(\Omega, \mathbb{V}) &\rightarrow L^2(\Omega, \mathbb{S}), \\ \boldsymbol{\phi} &\rightarrow \text{Div}^* \boldsymbol{\phi} = \boldsymbol{\Phi}, \end{aligned}$$

such that

$$\begin{aligned} \langle \text{Div } \boldsymbol{\Psi}, \boldsymbol{\phi} \rangle_{L^2(\Omega, \mathbb{V})} &= \langle \boldsymbol{\Psi}, \text{Div}^* \boldsymbol{\phi} \rangle_{L^2(\Omega, \mathbb{S})}, & \forall \boldsymbol{\Psi} \in \text{Dom}(\text{Div}) \subset L^2(\Omega, \mathbb{S}), \\ & & \forall \boldsymbol{\phi} \in \text{Dom}(\text{Div}^*) \subset L^2(\Omega, \mathbb{V}). \end{aligned}$$

Now let us take $\boldsymbol{\Psi} \in C_0^1(\Omega, \mathbb{S}) \subset \text{Domain}(\text{Div})$ the space of differentiable symmetric tensors

with compact support in Ω . Additionally ϕ will belong to $C_0^1(\Omega, \mathbb{V}) \subset \text{Dom}(\text{Div}^*)$, the space of differentiable vector functions with compact support in Ω . Then

$$\begin{aligned}
 \langle \text{Div } \Psi, \phi \rangle_{L^2(\Omega, \mathbb{V})} &= \int_{\Omega} \psi \cdot \phi \, d\Omega, \\
 &= \int_{\Omega} \sum_{i=1}^d \sum_{j=1}^d \frac{\partial \Psi_{ij}}{\partial x_i} \phi_j \, d\Omega, \\
 &= - \int_{\Omega} \sum_{i=1}^d \sum_{j=1}^d \Psi_{ij} \frac{\partial \phi_j}{\partial x_i} \, d\Omega, \quad \text{since the functions vanish at the boundary,} \\
 &= - \int_{\Omega} \sum_{i=1}^d \sum_{j=1}^d \Psi_{ij} F_{ij} \, d\Omega, \quad \text{where } F_{ij} = \frac{\partial \phi_j}{\partial x_i}, \\
 &= - \langle \Psi, \mathbf{F} \rangle_{L^2(\Omega, \mathbb{S})}, \quad \mathbf{F} = \text{grad } \phi.
 \end{aligned}$$

583 But in this latter case, it could not be stated that $\mathbf{F} \in L^2(\Omega, \mathbb{S})$. Now, since $\Psi \in L^2(\Omega, \mathbb{S})$,
 584 $\Psi_{ji} = \Psi_{ij}$, thus the last equality can be further decomposed as

$$\sum_{i,j} \Psi_{ij} \frac{\partial \phi_j}{\partial x_i} = \sum_{i,j} \Psi_{ij} \frac{1}{2} \left(\frac{\partial \phi_i}{\partial x_j} + \frac{\partial \phi_j}{\partial x_i} \right) = \sum_{i,j} \Psi_{ij} \Phi_{ij}, \quad \text{with } \Phi_{ij} := \frac{1}{2} \left(\frac{\partial \phi_i}{\partial x_j} + \frac{\partial \phi_j}{\partial x_i} \right).$$

Thus $\Phi = \text{Grad } \phi \in L^2(\Omega, \mathbb{S})$ and it can be stated that:

$$\begin{aligned}
 \langle \text{Div } \Psi, \phi \rangle_{L^2(\Omega, \mathbb{V})} &= - \int_{\Omega} \sum_{i,j} \Psi_{ij} \frac{1}{2} \left(\frac{\partial \phi_i}{\partial x_j} + \frac{\partial \phi_j}{\partial x_i} \right) \, d\Omega \\
 &= - \int_{\Omega} \sum_{i,j} \Psi_{ij} \Phi_{ij} \, d\Omega = \langle \Psi, -\text{Grad } \phi \rangle_{L^2(\Omega, \mathbb{S})}.
 \end{aligned}$$

585 It can be concluded that the formal adjoint of Div is $\text{Div}^* = -\text{Grad}$. □

586 The boundary values are then found by evaluating the energy rate

$$\begin{aligned}
 \dot{H} &= \int_{\Omega} \{ \mathbf{e}_v \cdot \partial_t \boldsymbol{\alpha}_v + \mathbf{E}_{\varepsilon} : \partial_t \mathbf{A}_{\varepsilon} \} \, d\Omega, \\
 &= \int_{\Omega} \{ \mathbf{e}_v \cdot \text{Div } \mathbf{E}_{\varepsilon} + \mathbf{E}_{\varepsilon} : \text{Grad } \mathbf{e}_v \} \, d\Omega, \\
 &= \int_{\Omega} \text{div}(\mathbf{E}_{\varepsilon} \mathbf{e}_v) \, d\Omega, \quad \text{Stokes theorem (see Appendix A Eq. (A.6)),} \\
 &= \int_{\partial\Omega} \mathbf{e}_v \cdot (\mathbf{E}_{\varepsilon} \mathbf{n}) \, dS = \langle \mathbf{e}_v, \mathbf{E}_{\varepsilon} \mathbf{n} \rangle_{L^2(\partial\Omega, \mathbb{R}^d)}.
 \end{aligned} \tag{4.15}$$

587 The imposition of the velocity field along the boundary $\mathbf{e}_v = \partial_t \mathbf{u}$ corresponds to a Dirichlet
 588 condition. Setting $\mathbf{E}_{\varepsilon} \mathbf{n} = \boldsymbol{\Sigma} \mathbf{n} = \mathbf{t}$ (the traction) corresponds to a Neumann condition.

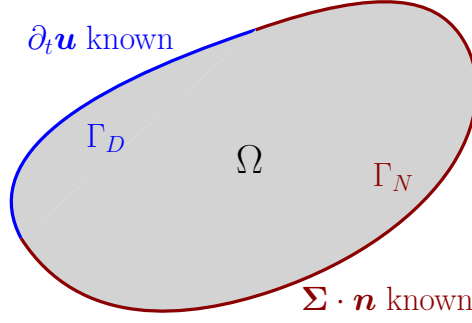


Figure 4.1: A 2D continuum with Neumann and Dirichlet boundary conditions

589 Consider a partition of the boundary $\partial\Omega = \bar{\Gamma}_N \cup \bar{\Gamma}_D$ and $\Gamma_N \cap \Gamma_D = \{\emptyset\}$, where a Dirichlet
 590 and a Neumann condition applies on the open subset Γ_D and Γ_N respectively (see Fig. 4.1).
 591 Then the final pH formulation reads

$$\begin{aligned}
 \frac{\partial}{\partial t} \begin{pmatrix} \alpha_v \\ \mathbf{A}_\varepsilon \end{pmatrix} &= \underbrace{\begin{bmatrix} \mathbf{0} & \text{Div} \\ \text{Grad} & \mathbf{0} \end{bmatrix}}_{\mathcal{J}} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix}, \\
 \mathbf{u}_\partial &= \underbrace{\begin{bmatrix} \gamma_0^{\Gamma_D} & \mathbf{0} \\ \mathbf{0} & \gamma_n^{\Gamma_N} \end{bmatrix}}_{\mathcal{B}_\partial} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix}, \\
 \mathbf{y}_\partial &= \underbrace{\begin{bmatrix} \mathbf{0} & \gamma_n^{\Gamma_D} \\ \gamma_0^{\Gamma_N} & \mathbf{0} \end{bmatrix}}_{\mathcal{C}_\partial} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix},
 \end{aligned} \tag{4.16}$$

592 where $\gamma_0^{\Gamma_*}$ denotes the trace over the set Γ_* , namely $\gamma_0^{\Gamma_*} \mathbf{e}_v = \mathbf{e}_v|_{\Gamma_*}$. Furthermore, $\gamma_n^{\Gamma_*}$ denotes
 593 the normal trace over the set Γ_* , namely $\gamma_n^{\Gamma_*} \mathbf{E}_\varepsilon = \mathbf{E}_\varepsilon \mathbf{n}|_{\Gamma_*}$.

Conjecture 1 (Stokes-Dirac structure for elastodynamics)

Let $H^{\text{Grad}}(\Omega, \mathbb{V})$ denote the space of vectors with symmetric gradient in $L^2(\Omega, \mathbb{S})$ and $H^{\text{Div}}(\Omega, \mathbb{S})$ be the space of symmetric tensors with divergence in $L^2(\Omega, \mathbb{V})$. Consider the following definitions

$$\begin{aligned}
 H &:= H^{\text{Grad}}(\Omega, \mathbb{V}) \times H^{\text{Div}}(\Omega, \mathbb{S}), \\
 F &:= L^2(\Omega, \mathbb{V}) \times L^2(\Omega, \mathbb{S}), \\
 F_\partial &:= L^2(\Gamma_D, \mathbb{V}) \times L^2(\Gamma_N, \mathbb{V}).
 \end{aligned}$$

594 The set

$$D_{\mathcal{J}} = \left\{ \begin{pmatrix} \mathbf{f} \\ \mathbf{f}_\partial \\ \mathbf{e} \\ \mathbf{e}_\partial \end{pmatrix} \mid \mathbf{e} \in H, \mathbf{f} = \mathcal{J}\mathbf{e}, \mathbf{f}_\partial = \mathcal{B}_\partial \mathbf{e}, \mathbf{e}_\partial = -\mathcal{C}_\partial \mathbf{e} \right\}, \tag{4.17}$$

where $\mathbf{e} = (\mathbf{e}_v, \mathbf{E}_\varepsilon)$ and $\mathcal{J}, \mathcal{B}_\partial, \mathcal{C}_\partial$ are defined in (4.16), is a Stokes–Dirac structure with respect to the pairing

$$\langle\langle (\mathbf{f}^1, \mathbf{f}_\partial^1, \mathbf{e}^1, \mathbf{e}_\partial^1), (\mathbf{f}^2, \mathbf{f}_\partial^2, \mathbf{e}^2, \mathbf{e}_\partial^2) \rangle\rangle := \langle \mathbf{e}^1, \mathbf{f}^2 \rangle_F + \langle \mathbf{e}^2, \mathbf{f}^1 \rangle_F + \langle \mathbf{e}_\partial^1, \mathbf{f}_\partial^2 \rangle_{F_\partial} + \langle \mathbf{e}_\partial^2, \mathbf{f}_\partial^1 \rangle_{F_\partial}, \quad (4.18)$$

where

$$\langle\langle (\mathbf{a}, \mathbf{b}), (\mathbf{c}, \mathbf{d}) \rangle\rangle_{F_\partial} = \int_{\Gamma_D} \mathbf{a} \cdot \mathbf{c} \, dS + \int_{\Gamma_N} \mathbf{b} \cdot \mathbf{d} \, dS, \quad \mathbf{a}, \mathbf{b}, \mathbf{c}, \mathbf{d} \in \mathbb{V}.$$

Crucial points to obtain a rigorous proof The crucial point that needs to be elucidated is where the boundary variables live. These variables belong to the fractional Sobolev spaces $H^{\frac{1}{2}}(\partial\Omega, \mathbb{V})$, $H^{-\frac{1}{2}}(\partial\Omega, \mathbb{V})$ linked by duality with respect to the pivot space $L^2(\partial\Omega, \mathbb{V})$. This is why a L^2 inner product has been assumed as boundary inner product. Furthermore, the partition of the boundary due to the non uniform boundary control complicates the proof, since one has to properly connect the two partitions at their interconnection.

Elements to support the conjecture A Stokes–Dirac is characterized by the fact that $D_{\mathcal{J}} = D_{\mathcal{J}}^\perp$. Then one has to show that $D_{\mathcal{J}} \subset D_{\mathcal{J}}^\perp$ and $D_{\mathcal{J}}^\perp \subset D_{\mathcal{J}}$. The main steps of Theorem 3.6 in [LGZM05] are followed here to support the substantiation of the conjecture. The integration by parts formula is applied as in (4.15).

Step 1. To show that $D_{\mathcal{J}} \subset D_{\mathcal{J}}^\perp$, take $(\mathbf{f}, \mathbf{f}_\partial, \mathbf{e}, \mathbf{e}_\partial) \in D_{\mathcal{J}}$. Then

$$\begin{aligned} \langle\langle (\mathbf{f}, \mathbf{f}_\partial, \mathbf{e}, \mathbf{e}_\partial), (\mathbf{f}, \mathbf{f}_\partial, \mathbf{e}, \mathbf{e}_\partial) \rangle\rangle &= 2 \langle \mathbf{e}, \mathbf{f} \rangle_F + 2 \langle \mathbf{e}_\partial, \mathbf{f}_\partial \rangle_{F_\partial}, \\ &= 2 \langle \mathbf{e}, \mathcal{J}\mathbf{e} \rangle_F + 2 \langle \mathbf{e}_\partial, \mathbf{f}_\partial \rangle_{F_\partial}, \\ &= 2 \int_{\Omega} \{ \mathbf{e}_v \cdot \text{Div } \mathbf{E}_\varepsilon + \mathbf{E}_\varepsilon : \text{Grad } \mathbf{e}_v \} \, d\Omega \\ &\quad - 2 \int_{\Gamma_D} \mathbf{e}_v \cdot (\mathbf{E}_\varepsilon \mathbf{n}) \, dS - 2 \int_{\Gamma_N} \mathbf{e}_v \cdot (\mathbf{E}_\varepsilon \mathbf{n}) \, dS, \\ &= 2 \int_{\Omega} \{ \mathbf{e}_v \cdot \text{Div } \mathbf{E}_\varepsilon + \mathbf{E}_\varepsilon : \text{Grad } \mathbf{e}_v \} \, d\Omega \\ &\quad - 2 \int_{\partial\Omega} \mathbf{e}_v \cdot (\mathbf{E}_\varepsilon \mathbf{n}) \, dS = 0, \quad \text{from (4.15)}. \end{aligned}$$

This implies $D_{\mathcal{J}} \subset D_{\mathcal{J}}^\perp$.

Step 2. Take $(\phi, \phi_\partial, \epsilon, \epsilon_\partial) \in D_{\mathcal{J}}^\perp$ and $\mathbf{e}_0 \in H$ with compact support on Ω . This implies $\mathcal{B}_\partial \mathbf{e}_0 = (\mathbf{0}, \mathbf{0})$ and $\mathcal{C}_\partial \mathbf{e}_0 = (\mathbf{0}, \mathbf{0})$. Taking $(\mathcal{J}\mathbf{e}_0, \mathbf{0}, \mathbf{e}_0, \mathbf{0}) \in D_{\mathcal{J}}$ then

$$\langle\langle (\phi, \phi_\partial, \epsilon, \epsilon_\partial), (\mathcal{J}\mathbf{e}_0, \mathbf{0}, \mathbf{e}_0, \mathbf{0}) \rangle\rangle = \langle \epsilon, \mathcal{J}\mathbf{e}_0 \rangle_F + \langle \mathbf{e}_0, \phi \rangle_F = 0, \quad \forall \mathbf{e}_0 \in H.$$

It follows that $\epsilon \in H$ and $\phi = \mathcal{J}\epsilon$.

Step 3. Take $(\phi, \phi_\partial, \epsilon, \epsilon_\partial) \in D_{\mathcal{J}}^\perp$ and $(\mathbf{f}, \mathbf{f}_\partial, \mathbf{e}, \mathbf{e}_\partial) \in D_{\mathcal{J}}$. Variables \mathbf{e}, ϵ are indeed tuples containing a vector and a tensor, namely $\mathbf{e} = (\mathbf{e}_v, \mathbf{E}_\epsilon)$, $\epsilon = (\epsilon_v, \mathcal{E}_\epsilon)$. From step 2 and (4.18)

$$\begin{aligned} 0 &= \langle \mathbf{e}, \mathcal{J}\epsilon \rangle_F + \langle \mathcal{J}\mathbf{e}, \epsilon \rangle_F + \langle \mathbf{e}_\partial, \phi_\partial \rangle_{F_\partial} + \langle \epsilon_\partial, \mathbf{f}_\partial \rangle_{F_\partial}, \\ &= \int_{\partial\Omega} \{ \mathbf{e}_v \cdot (\mathcal{E}_\epsilon \cdot \mathbf{n}) + \epsilon_v \cdot (\mathbf{E}_\epsilon \cdot \mathbf{n}) \} \, dS + \langle -\mathcal{C}_\partial \mathbf{e}, \phi_\partial \rangle_{F_\partial} + \langle \epsilon_\partial, \mathcal{B}_\partial \mathbf{e} \rangle_{F_\partial} \end{aligned}$$

Consider the splitting of the boundary $\partial\Omega = \bar{\Gamma}_N \cup \bar{\Gamma}_D$

$$\begin{aligned} \int_{\partial\Omega} \{ \mathbf{e}_v \cdot (\mathcal{E}_\epsilon \cdot \mathbf{n}) + \epsilon_v \cdot (\mathbf{E}_\epsilon \cdot \mathbf{n}) \} \, dS &= + \int_{\Gamma_N} \{ \mathbf{e}_{\partial,2} \cdot (\mathcal{E}_\epsilon \cdot \mathbf{n}) + \epsilon_v \cdot \mathbf{f}_{\partial,2} \} \, dS, \\ &+ \int_{\Gamma_D} \{ \mathbf{f}_{\partial,1} \cdot (\mathcal{E}_\epsilon \cdot \mathbf{n}) + \epsilon_v \cdot \mathbf{e}_{\partial,1} \} \, dS, \end{aligned}$$

where the elements of the vectors $\mathbf{f}_\partial = (\mathbf{f}_{\partial,1}, \mathbf{f}_{\partial,2})$, $\mathbf{e}_\partial = (\mathbf{e}_{\partial,1}, \mathbf{e}_{\partial,2})$ have been considered. By expanding of the terms $\langle \mathbf{e}_\partial, \phi_\partial \rangle_{F_\partial} + \langle \epsilon_\partial, \mathbf{f}_\partial \rangle_{F_\partial}$ and given the fact that \mathbf{e} is arbitrary then

$$\phi_\partial = \begin{bmatrix} \gamma_0^{\Gamma_D} & \mathbf{0} \\ \mathbf{0} & \gamma_n^{\Gamma_N} \end{bmatrix} \begin{pmatrix} \epsilon_v \\ \mathcal{E}_\epsilon \end{pmatrix}, \quad \epsilon_\partial = - \begin{bmatrix} \mathbf{0} & \gamma_n^{\Gamma_D} \\ \gamma_0^{\Gamma_N} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \epsilon_v \\ \mathcal{E}_\epsilon \end{pmatrix},$$

meaning that $D_{\mathcal{J}}^\perp \subset D_{\mathcal{J}}$.

Linear elasticity falls within the assumption of [Skr19]. Therefore, it is a well posed boundary control pH system. A question that naturally arises is how to reformulate this system using the language of differential geometry. This is possible through the usage of vector-valued differential forms. The interested reader may consult [Bre08].

4.3 Conclusion

In this chapter, the pH formulation of elasticity has been obtained. This model represents a generalization of the wave equation to higher dimensional variables. This leads to the introduction of symmetric tensorial quantities describing the state of stress and deformation within the body.

For a plane continuum with moderate thickness, it is possible to reduce the general three-dimensional mode to two uncoupled systems: one representing the in-plane behavior ruled by 2D elasticity and one representing the out-of-plane deflection. This will be the object of the next chapter dedicated to the study of a pH formulation of plate bending. It is important to remember that plate models are just particular cases of three-dimensional elasticity.

Port-Hamiltonian plate theory

You get tragedy where the tree, instead of bending, breaks.

Culture and Value
Ludwig Wittgenstein

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lates are plane structural elements with a small thickness compared to the planar dimensions. Thanks to this feature, it is not necessary to model plate structures using three-dimensional elasticity. Dimensional reduction strategies are employed to describe plate structures as two-dimensional problems. These strategies rely on an educated guess of the displacement field. For beams and plates this field is expressed in terms of unknown functions $\phi_i^j(x, y, t)$ that solely depends on the midplane coordinates (x, y)

$$u_i(x, y, z, t) = \sum_{j=0}^m (z)^j \phi_i^j(x, y, t).$$

where u_i , $i = \{x, y, z\}$ are the components of the displacement field. A first-order approximation is commonly used, meaning that a linear dependence on z is considered. Two main models arise from such a framework:

- the Mindlin-Reissner model for thick plates;

- the Kirchhoff-Love model for thin plates.

In this chapter it is shown how to formulate first-order plate models as pHs.

5.1 First order plate theory

As previously stated, first order theories assume a linear dependence on the vertical coordinate (cf. [Red06])

$$u_i(x, y, z, t) = \phi_i^0(x, y, t) + z\phi_i^1(x, y, t).$$

This hypothesis implies that the fibers, i.e. segments perpendicular to the mid-plane before deformation, remain straight after deformation. Additionally, for plate with moderate thickness the fibers are considered inextensible, meaning that $\phi_z^1 = 0$. These assumptions lead to the following displacement field

$$\begin{aligned} u_x(x, y, z, t) &= u_x^0(x, y, t) - z\theta_x(x, y, t), \\ u_y(x, y, z, t) &= u_y^0(x, y, t) - z\theta_y(x, y, t), \\ u_z(x, y, z, t) &= u_z^0(x, y, t), \end{aligned} \tag{5.1}$$

where $u_i^0(x, y, t) = \phi_i^0(x, y, t)$, $\theta_i(x, y, t) = -\phi_i^1(x, y, t)$. Assuming a linear elastic behavior, the 3D strain tensors for such a displacement field takes the form

$$\varepsilon_{\alpha\beta} = \frac{1}{2}(\partial_\beta u_\alpha + \partial_\alpha u_\beta) - z\frac{1}{2}(\partial_\beta \theta_\alpha + \partial_\alpha \theta_\beta) = \varepsilon_{\alpha\beta}^0 - z\kappa_{\alpha\beta}, \tag{5.2}$$

$$\varepsilon_{\alpha z} = \frac{1}{2}(\partial_\alpha u_z - \theta_\alpha) = \frac{1}{2}\gamma_\alpha, \tag{5.3}$$

where $\alpha = \{x, y\}$, $\beta = \{x, y\}$. The tensors ε^0 , κ , γ are called membrane, bending (or curvature) and shear strain tensor

$$\varepsilon^0 = \text{Grad } \mathbf{u}^0, \tag{5.4}$$

$$\kappa = \text{Grad } \boldsymbol{\theta}, \tag{5.5}$$

$$\gamma = \text{grad } u_z - \boldsymbol{\theta}. \tag{5.6}$$

where $\mathbf{u}^0 = (u_x, u_y)^\top$, $\boldsymbol{\theta} = (\theta_x, \theta_y)^\top$. For now, it is assumed that the material is isotropic, linear elastic (in Section §5.3 this hypothesis is removed). Recall the Hooke's law for 3D continua (see Eq. (4.5))

$$\boldsymbol{\Sigma} = \frac{E}{1+\nu} \left[\boldsymbol{\varepsilon} + \frac{\nu}{1-2\nu} \text{Tr}(\boldsymbol{\varepsilon}) \mathbf{I}_{3 \times 3} \right].$$

where E , ν are the Young modulus and Poisson ratio. The hypothesis of inextensible fibers implies $\varepsilon_{zz} = 0$. However, imposing a plane strain condition provides a model that is too stiff. Rather than a plain strain assumption, a plain stress hypothesis is used to derive the constitutive law for plates. The displacement field (5.1) is left unchanged, but, instead of ε_{zz} ,

Σ_{zz} is set to zero. If $\Sigma_{zz} = 0$, one gets

$$\varepsilon_{zz} = -\frac{\nu}{1-\nu}(\varepsilon_{xx} + \varepsilon_{yy}).$$

Consequently, it is computed

$$\text{Tr}(\boldsymbol{\varepsilon}) = \frac{1-2\nu}{1-\nu}(\varepsilon_{xx} + \varepsilon_{yy}).$$

The constitutive law for the in-plane stress takes the form

$$\boldsymbol{\Sigma}_{2D} = \boldsymbol{\mathcal{D}}_{2D} \boldsymbol{\varepsilon}_{2D},$$

659 where $\boldsymbol{\Sigma}_{2D} = \Sigma_{\alpha\beta}$, $\boldsymbol{\varepsilon}_{2D} = \varepsilon_{\alpha\beta}$ and

$$\boldsymbol{\mathcal{D}}_{2D} = \frac{E}{1-\nu^2} [(1-\nu)(\cdot) + \nu \text{Tr}(\cdot) \mathbf{I}_{2 \times 2}]. \quad (5.7)$$

660 Concerning the shear deformation, the constitutive law reduces to

$$\boldsymbol{\sigma}_s = G\boldsymbol{\gamma}, \quad (5.8)$$

661 where $\boldsymbol{\sigma}_s := \boldsymbol{\Sigma}_{\alpha,3}$ and $G = \frac{E}{2(1+\nu)}$ is the shear modulus. In the following sections, the most
662 common plate models will be presented.

663 5.1.1 Mindlin-Reissner model

664 The Mindlin-Reissner model [Rei47, Min51] represents a first-order shear deformation theory
665 for describing the bending of plate. The in-plane midplane displacement are zero $\mathbf{u}^0(x, y) = \mathbf{0}$
666 for an isotropic plate that experiences only bending. Hence, the displacement field reduces to

$$\begin{aligned} u_x(x, y, z) &= -z\partial_x\theta_x, \\ u_y(x, y, z) &= -z\partial_y\theta_y, \\ u_z(x, y, z) &= u_z^0(x, y). \end{aligned} \quad (5.9)$$

In pure bending, the strain tensor is given by

$$\boldsymbol{\varepsilon}_b := \boldsymbol{\varepsilon}_{2D}(\mathbf{u}^0 = \mathbf{0}) = -z\boldsymbol{\kappa},$$

with $\boldsymbol{\kappa}$ given by (5.5). Consequently, the stress tensor reads

$$\boldsymbol{\Sigma}_b := \boldsymbol{\Sigma}_{2D}(\mathbf{u}^0 = \mathbf{0}) = -z\boldsymbol{\mathcal{D}}_{2D}\boldsymbol{\kappa},$$

667 where $\boldsymbol{\mathcal{D}}_{2D}$ is defined in Eq. (5.7).
668

669 The undeformed middle plane of the plate is denoted by Ω . The total domain of the

plate is the product $\Omega \times (-h/2, h/2)$, where h is the constant thickness. To effectively reduce the problem from three- to two-dimensional, the stresses have to be integrated along the fibers. Since the stress varies linearly across the thickness, the stress has to be multiplied by z before the integration to get a non null contribution. The resulting quantity is called bending momenta tensor and is given by

$$\mathbf{M} := - \int_{-h/2}^{h/2} z \boldsymbol{\Sigma}_b \, dz = \mathcal{D}_b \boldsymbol{\kappa}, \quad (5.10)$$

where

$$\mathcal{D}_b = D_b [(1 - \nu)(\cdot) + \nu \operatorname{Tr}(\cdot) \mathbf{I}_{2 \times 2}], \quad \text{where} \quad D_b = \frac{Eh^3}{12(1 - \nu^2)}. \quad (5.11)$$

The shear stress has to be integrated along the fibers as well. Given the excessive rigidity of the shear contribution, a correction factor $K_{\text{sh}} = 5/6$ [Red06, Chapter 10] is introduced

$$\mathbf{q} = \int_{-h/2}^{h/2} K_{\text{sh}} \boldsymbol{\sigma}_s \, dz = K_{\text{sh}} Gh \boldsymbol{\gamma}, \quad (5.12)$$

where $\boldsymbol{\gamma}$ is defined in Eq. (5.6). The equations of motion can be obtained using Hamilton's principle. It consists in minimizing the total Lagrangian, given by $L = E_{\text{def}} - E_{\text{kin}}$, where E_{def} and E_{kin} are the deformation and kinetic energies

$$E_{\text{def}} = \frac{1}{2} \int_{\Omega} \int_{-h/2}^{h/2} \boldsymbol{\Sigma} : \boldsymbol{\varepsilon} \, d\Omega \, dz = \frac{1}{2} \int_{\Omega} \{ \mathbf{M} : \boldsymbol{\kappa} + \mathbf{q} \cdot \boldsymbol{\gamma} \} \, d\Omega, \quad (5.13)$$

$$E_{\text{kin}} = \frac{1}{2} \int_{\Omega} \int_{-h/2}^{h/2} \rho \|\partial_t \mathbf{u}\|^2 \, d\Omega \, dz = \frac{1}{2} \int_{\Omega} \left\{ \frac{\rho h^3}{12} \|\partial_t \boldsymbol{\theta}\|^2 + \rho h (\partial_t u_z)^2 \right\} \, d\Omega, \quad (5.14)$$

where ρ is the mass density. The Hamilton principle states that

$$\int_0^T \delta L \, dt = \int_0^T \{ \delta E_{\text{def}} - \delta E_{\text{kin}} \} \, dt = 0.$$

The final result is the following system of PDEs (for the detailed computations see [Red06, Chapter 10])

$$\begin{aligned} \rho h \frac{\partial^2 u_z}{\partial t^2} &= \operatorname{div} \mathbf{q}, & (x, y) \in \Omega, \\ \frac{\rho h^3}{12} \frac{\partial^2 \boldsymbol{\theta}}{\partial t^2} &= \operatorname{Div} \mathbf{M} + \mathbf{q}, \end{aligned} \quad (5.15)$$

with $\mathbf{M} = \mathcal{D}_b \operatorname{Grad} \boldsymbol{\theta}$ and $\mathbf{q} = K_{\text{sh}} Gh (\operatorname{grad} u_z - \boldsymbol{\theta})$. This PDE goes together with specified boundary conditions. Those will be detailed in 5.2.1.

5.1.2 Kirchhoff-Love model

The Kirchhoff model was formulated around 1850 and it is referred to as classical plate theory. The hypotheses on the displacement field consist of the following three points (see Fig. 5.1):

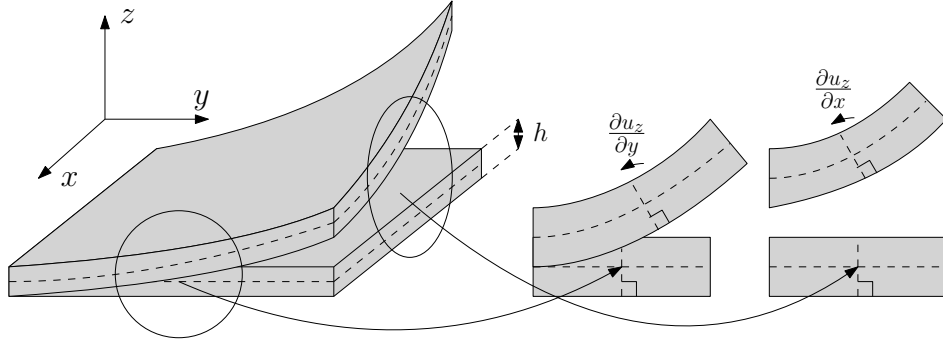


Figure 5.1: Kinematic assumption for the Kirchhoff plate

1. The fibers, segments perpendicular to the mid-plane before deformation, remain straight after deformation.
2. The fibers are inextensible.
3. While rotating, fibers remain perpendicular to the middle surface after deformation.

While the first two points are valid also for the Mindlin plate, the third assumption is specific to the Kirchhoff-Love model. Such an approximation is valid for plates having span-to-thickness ratio of the order of $L/h \approx 100 - 1000$ and implies zero transverse shear deformation

$$\gamma = 0 \implies \varepsilon_{xz} = -\theta_x + \frac{\partial u_z}{\partial x} = 0, \quad \varepsilon_{yz} = -\theta_y + \frac{\partial u_z}{\partial y} = 0.$$

The rotation vector is then related to the vertical displacement $\boldsymbol{\theta} = \text{grad } u_z$. Plugging this into (5.5), it is found

$$\boldsymbol{\kappa} = \text{Grad grad } u_z = \text{Hess } u_z. \quad (5.16)$$

Since the focus is on bending behavior, the in-plane displacement of the mid-plane are assumed to be zero $\mathbf{u}^0(x, y) = \mathbf{0}$. Hence, the displacement field assumes the form

$$\begin{aligned} u_x(x, y, z) &= -z \partial_x u_z, \\ u_y(x, y, z) &= -z \partial_y u_z, \\ u_z(x, y, z) &= u_z^0(x, y). \end{aligned} \quad (5.17)$$

For the Kirchhoff plate, the same link between the momenta and bending tensor holds

$$\mathbf{M} = \mathcal{D}_b \boldsymbol{\kappa},$$

where \mathcal{D}_b and $\boldsymbol{\kappa}$ are given in (5.11), (5.16) respectively. The equations of motion can be obtained using Hamilton's principle [Red06, Chapter 2]. The deformation energy, kinetic

energy and external work read

$$E_{\text{def}} = \frac{1}{2} \int_{\Omega} \int_{-h/2}^{h/2} \boldsymbol{\Sigma} : \boldsymbol{\varepsilon} \, d\Omega \, dz = \frac{1}{2} \int_{\Omega} \{ \mathbf{M} : \boldsymbol{\kappa} \} \, d\Omega, \quad (5.18)$$

$$E_{\text{kin}} = \frac{1}{2} \int_{\Omega} \int_{-h/2}^{h/2} \rho \, \|\partial_t \mathbf{u}\|^2 \, d\Omega \, dz \approx \frac{1}{2} \int_{\Omega} \rho h (\partial_t u_z)^2 \, d\Omega. \quad (5.19)$$

Remark 4 (Rotational energy)

For the kinetic energy the rotational contribution

$$E_{\text{rot}} = \frac{1}{2} \int_{\Omega} \int_{-h/2}^{h/2} \left\{ \rho (\partial_t u_x)^2 + (\partial_t u_y)^2 \right\} \, d\Omega \, dz = \frac{h^3}{24} \int_{\Omega} \rho \left\{ (\partial_{tx} u_z)^2 + (\partial_{ty} u_z)^2 \right\} \, d\Omega = O(h^3),$$

is neglected given the small thickness assumption.

The final result from the Hamilton's principle is the following PDE (for the detailed computations the reader may consult [Red06, Chapter 3])

$$\rho h \frac{\partial^2 u_z}{\partial t^2} = -\operatorname{div} \operatorname{Div}(\mathcal{D}_b \operatorname{Grad} \operatorname{grad} u_z), \quad (x, y) \in \Omega. \quad (5.20)$$

Developing the calculations, one obtains

$$\rho h \frac{\partial^2 u_z}{\partial t^2} = -D_b \Delta^2 u_z, \quad (x, y) \in \Omega,$$

where $\Delta^2 = \frac{\partial^4}{\partial x^4} + 2 \frac{\partial^2}{\partial x^2} \frac{\partial^2}{\partial y^2} + \frac{\partial^4}{\partial y^4}$ is the bi-Laplacian. Appropriate boundary conditions for this problem will be detailed in 5.2.2.

5.2 Port-Hamiltonian formulation of isotropic plates

In this section the pH formulation of the isotropic Mindlin and Kirchhoff plate models is detailed. In [MMB05], the Mindlin plate model was put in pH form by appropriate selection of the energy variables. However, the final system does not consider the nature of the different variables that come into play, leading to a non intrinsic final formulation. Additionally, this model was presented using the jet bundle formalism in [SS17]. The Kirchhoff model was never explored in the pH framework and represents an original contribution of this thesis. The interested reader can find in [RZ18] a rigorous mathematical treatment of the biharmonic problem and its decomposition in 2D geometries, but only for the static case (the 3D case, that does not relate to plate bending, is treated in [DZ18]).

5.2.1 Port-Hamiltonian Mindlin plate

Let $w := u_z$ denote the vertical displacement of the plate. Consider a bounded, connected domain $\Omega \subset \mathbb{R}^2$ and the Hamiltonian (total energy)

$$H = \frac{1}{2} \int_{\Omega} \left\{ \rho h \left(\frac{\partial w}{\partial t} \right)^2 + \frac{\rho h^3}{12} \left\| \frac{\partial \boldsymbol{\theta}}{\partial t} \right\|^2 + \mathbf{M} : \boldsymbol{\kappa} + \mathbf{q} \cdot \boldsymbol{\gamma} \right\} d\Omega, \quad (5.21)$$

where \mathbf{M} , $\boldsymbol{\kappa}$, \mathbf{q} , $\boldsymbol{\gamma}$ are defined in Eqs. (5.10), (5.5), (5.12), (5.6) respectively. The choice of the energy variables is the same as in [MMB05] but here scalar-, vector- and tensor-valued variables are gathered together:

$$\begin{aligned} \alpha_w &= \rho h \frac{\partial w}{\partial t}, & \text{Linear momentum,} & & \alpha_{\theta} &= \frac{\rho h^3}{12} \frac{\partial \boldsymbol{\theta}}{\partial t}, & \text{Angular momentum,} \\ \mathbf{A}_{\kappa} &= \boldsymbol{\kappa}, & \text{Curvature tensor,} & & \boldsymbol{\alpha}_{\gamma} &= \boldsymbol{\gamma}. & \text{Shear deformation.} \end{aligned} \quad (5.22)$$

The energy is now a quadratic function of the energy variables

$$H = \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\rho h} \alpha_w^2 + \frac{12}{\rho h^3} \|\alpha_{\theta}\|^2 + (\mathcal{D}_b \mathbf{A}_{\kappa}) : \mathbf{A}_{\kappa} + (\mathcal{D}_s \boldsymbol{\alpha}_{\gamma}) \cdot \boldsymbol{\alpha}_{\gamma} \right\} d\Omega, \quad (5.23)$$

where $\mathcal{D}_s := GhK_{\text{sh}} \mathbf{I}_{2 \times 2}$, G is the shear modulus and K_{sh} the correction factor. The co-energy variables are found by computing the variational derivative of the Hamiltonian:

$$\begin{aligned} e_w &:= \frac{\delta H}{\delta \alpha_w} = \frac{\partial w}{\partial t}, & \text{Linear velocity,} & & e_{\theta} &:= \frac{\delta H}{\delta \alpha_{\theta}} = \frac{\partial \boldsymbol{\theta}}{\partial t}, & \text{Angular velocity,} \\ \mathbf{E}_{\kappa} &:= \frac{\delta H}{\delta \mathbf{A}_{\kappa}} = \mathbf{M}, & \text{Momenta tensor,} & & \mathbf{e}_{\gamma} &:= \frac{\delta H}{\delta \boldsymbol{\alpha}_{\gamma}} = \mathbf{q} & \text{Shear stress.} \end{aligned} \quad (5.24)$$

Proposition 4

The variational derivative of the Hamiltonian with respect to the curvature tensor is the momenta tensor $\frac{\delta H}{\delta \mathbf{A}_{\kappa}} = \mathbf{M}$.

Proof. The proof is analogous to the one already detailed in Prop. 3 □

Once the variables are concatenated together, the pH system is expressed as follows

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \alpha_{\theta} \\ \mathbf{A}_{\kappa} \\ \boldsymbol{\alpha}_{\gamma} \end{pmatrix} = \begin{bmatrix} 0 & 0 & 0 & \text{div} \\ \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{I}_{2 \times 2} \\ \mathbf{0} & \text{Grad} & \mathbf{0} & \mathbf{0} \\ \text{grad} & -\mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ e_{\theta} \\ \mathbf{E}_{\kappa} \\ e_{\gamma} \end{pmatrix}. \quad (5.25)$$

The first two equations are equivalent to (5.15). The last two equations, like (4.14) for 3D elasticity, represent the fact that the higher order derivatives commute. We shall now establish the total energy balance in terms of boundary variables as they will be part of the

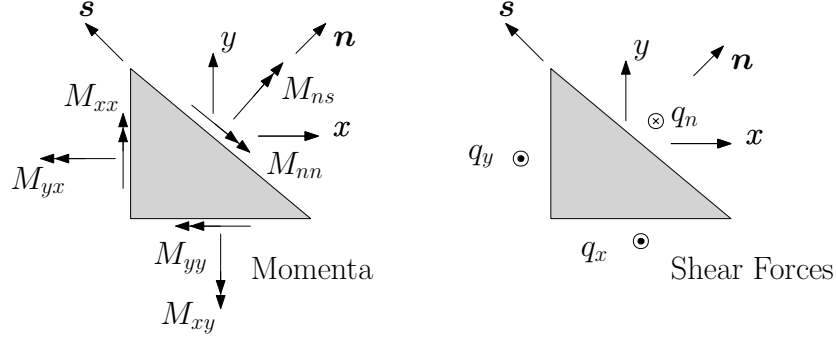


Figure 5.2: Cauchy law for momenta and forces at the boundary.

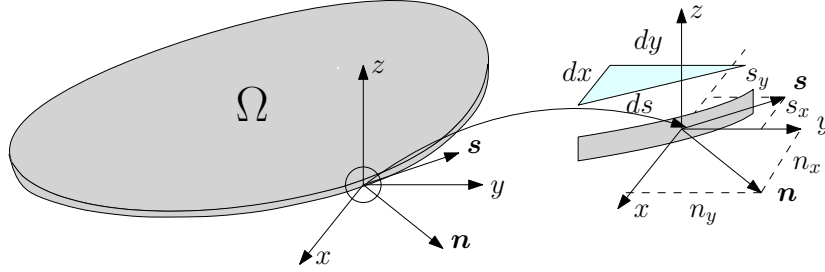


Figure 5.3: Reference frames and notations.

underlying Stokes-Dirac structure of this model. The energy rate reads

$$\begin{aligned}
 \dot{H} &= \int_{\Omega} \left\{ \frac{\partial \alpha_w}{\partial t} e_w + \frac{\partial \alpha_\theta}{\partial t} \cdot \mathbf{e}_\theta + \frac{\partial \mathbf{A}_\kappa}{\partial t} : \mathbf{E}_\kappa + \frac{\partial \alpha_\gamma}{\partial t} \cdot \mathbf{e}_\gamma \right\} d\Omega \\
 &= \int_{\Omega} \{ \operatorname{div}(\mathbf{e}_\gamma) e_w + \operatorname{Div}(\mathbf{E}_\kappa) \cdot \mathbf{e}_\theta + \operatorname{Grad}(\mathbf{e}_\theta) : \mathbf{E}_\kappa + \operatorname{grad}(e_w) \cdot \mathbf{e}_\gamma \} d\Omega \quad \text{Stokes theorem,} \\
 &= \int_{\partial\Omega} \{ w_t q_n + \omega_n M_{nn} + \omega_s M_{ns} \} ds,
 \end{aligned} \tag{5.26}$$

where s is the curvilinear abscissa. The last integral is obtained by applying the Stokes theorem. The boundary variables appearing in the last line of (5.26) and illustrated in Fig. 5.2 are defined as follows:

$$\begin{aligned}
 \text{Shear force} \quad q_n &:= \mathbf{q} \cdot \mathbf{n} = \mathbf{e}_\gamma \cdot \mathbf{n}, \\
 \text{Flexural momentum} \quad M_{nn} &:= \mathbf{M} : (\mathbf{n} \otimes \mathbf{n}) = \mathbf{E}_\kappa : (\mathbf{n} \otimes \mathbf{n}), \\
 \text{Torsional momentum} \quad M_{ns} &:= \mathbf{M} : (\mathbf{s} \otimes \mathbf{n}) = \mathbf{E}_\kappa : (\mathbf{s} \otimes \mathbf{n}),
 \end{aligned} \tag{5.27}$$

Vectors \mathbf{n} and \mathbf{s} designate the normal and tangential unit vectors to the boundary, as shown in Fig. 5.3. Given two vectors $\mathbf{a} \in \mathbb{R}^n$, $\mathbf{b} \in \mathbb{R}^m$, the notation $\mathbf{a} \otimes \mathbf{b} = \mathbf{a} \mathbf{b}^\top \in \mathbb{R}^{n \times m}$ denotes the

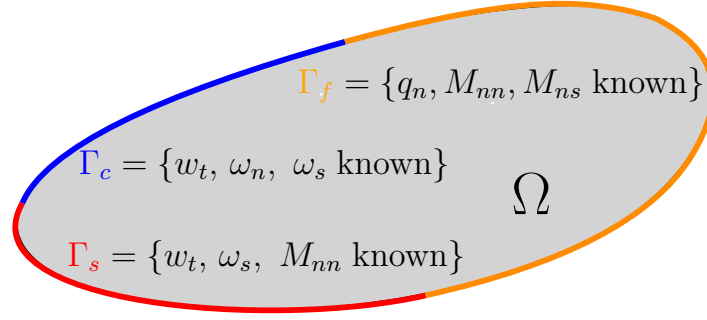


Figure 5.4: Boundary conditions for the Mindlin plate.

outer (or dyadic) product of two vectors. The corresponding power conjugated variables are

$$\begin{aligned}
 \text{Vertical velocity} \quad w_t &:= \frac{\partial w}{\partial t} = e_w, \\
 \text{Flexural rotation} \quad \omega_n &:= \frac{\partial \boldsymbol{\theta}}{\partial t} \cdot \mathbf{n} = \mathbf{e}_\theta \cdot \mathbf{n}, \\
 \text{Torsional rotation} \quad \omega_s &:= \frac{\partial \boldsymbol{\theta}}{\partial t} \cdot \mathbf{s} = \mathbf{e}_\theta \cdot \mathbf{s}.
 \end{aligned} \tag{5.28}$$

Consider a partition of the boundary $\partial\Omega = \bar{\Gamma}_C \cup \bar{\Gamma}_S \cup \bar{\Gamma}_F$, $\Gamma_C \cap \Gamma_S \cap \Gamma_F = \{\emptyset\}$. The open subset Γ_C , Γ_S , Γ_F could be empty. Given definitions (5.27), (5.28), the boundary conditions for the Mindlin plate [DHNLS99] (see Fig. 5.4) that are considered are:

- Clamped (C) on $\Gamma_C \subseteq \partial\Omega$: w_t , ω_n , ω_s known;
- Simply supported hard (S) on $\Gamma_S \subseteq \partial\Omega$: w_t , ω_s , M_{nn} known;
- Free (F) on $\Gamma_F \subseteq \partial\Omega$: M_{nn} , M_{ns} , q_n known.

Then the final pH formulation reads

$$\begin{aligned}
\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \boldsymbol{\alpha}_\theta \\ \mathbf{A}_\kappa \\ \boldsymbol{\alpha}_\gamma \end{pmatrix} &= \underbrace{\begin{bmatrix} 0 & 0 & 0 & \text{div} \\ \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{I}_{2 \times 2} \\ \mathbf{0} & \text{Grad} & \mathbf{0} & \mathbf{0} \\ \text{grad} & -\mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} \end{bmatrix}}_{\mathcal{J}} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ e_\gamma \end{pmatrix}, \\
\mathbf{u}_\partial &= \underbrace{\begin{bmatrix} \gamma_0^{\Gamma^C} & 0 & 0 & 0 \\ 0 & \gamma_n^{\Gamma^C} & 0 & 0 \\ 0 & \gamma_s^{\Gamma^C} & 0 & 0 \\ \gamma_0^{\Gamma^S} & 0 & 0 & 0 \\ 0 & \gamma_s^{\Gamma^S} & 0 & 0 \\ 0 & 0 & \gamma_{nn}^{\Gamma^S} & 0 \\ 0 & 0 & \gamma_{nn}^{\Gamma^F} & 0 \\ 0 & 0 & \gamma_{ns}^{\Gamma^F} & 0 \\ 0 & 0 & 0 & \gamma_n^{\Gamma^F} \end{bmatrix}}_{\mathcal{B}_\partial} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ e_\gamma \end{pmatrix}, \\
\mathbf{y}_\partial &= \underbrace{\begin{bmatrix} 0 & 0 & 0 & \gamma_n^{\Gamma^C} \\ 0 & 0 & \gamma_{nn}^{\Gamma^C} & 0 \\ 0 & 0 & \gamma_{ns}^{\Gamma^C} & 0 \\ 0 & 0 & 0 & \gamma_n^{\Gamma^S} \\ 0 & 0 & \gamma_{ns}^{\Gamma^S} & 0 \\ 0 & \gamma_n^{\Gamma^S} & 0 & 0 \\ 0 & \gamma_n^{\Gamma^F} & 0 & 0 \\ 0 & \gamma_s^{\Gamma^F} & 0 & 0 \\ \gamma_0^{\Gamma^F} & 0 & 0 & 0 \end{bmatrix}}_{\mathcal{C}_\partial} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ e_\gamma \end{pmatrix},
\end{aligned} \tag{5.29}$$

739 where $\gamma_0^{\Gamma^*} a = a|_{\Gamma^*}$ denotes the trace over the set Γ^* . Furthermore, notations $\gamma_n^{\Gamma^*} \mathbf{a} = \mathbf{a} \cdot$
 740 $\mathbf{n}|_{\Gamma^*}$, $\gamma_s^{\Gamma^*} \mathbf{a} = \mathbf{a} \cdot \mathbf{s}|_{\Gamma^*}$ indicate respectively the normal and tangential traces over the set
 741 Γ^* . Symbols $\gamma_{nn}^{\Gamma^*}, \gamma_{ns}^{\Gamma^*}$ denote the normal-normal trace and the normal-tangential trace of
 742 tensor-valued functions and $\gamma_{nn}^{\Gamma^*} \mathbf{A} = \mathbf{A} : (\mathbf{n} \otimes \mathbf{n})|_{\Gamma^*}$, $\gamma_{ns}^{\Gamma^*} \mathbf{A} = \mathbf{A} : (\mathbf{n} \otimes \mathbf{s})|_{\Gamma^*}$.

743 **Remark 5**

744 It can be observed that the interconnection structure given by \mathcal{J} in (5.29) mimics that of the
 745 Timoshenko beam [JZ12, Chapter 7].

Conjecture 2 (Stokes-Dirac structure for the Mindlin plate)

Consider $\mathbb{V} = \mathbb{R}^2$, $\mathbb{S} = \mathbb{R}_{sym}^{2 \times 2}$ and let $H^1(\Omega)$ be the space of functions with gradient in $L^2(\Omega, \mathbb{V})$
 and $H^{\text{div}}(\Omega, \mathbb{V})$ the space of vector-valued functions with divergence in $L^2(\Omega)$. Furthermore,
 $H^1(\Omega, \mathbb{V})$ is the space of vectors with symmetric gradient in $L^2(\Omega, \mathbb{S})$ and $H^{\text{Div}}(\Omega, \mathbb{S})$ denotes

the space of symmetric tensors with divergence in $L^2(\Omega, \mathbb{V})$. Consider the definitions

$$\begin{aligned} H &:= H^1(\Omega) \times H^{\text{Grad}}(\Omega, \mathbb{V}) \times H^{\text{Div}}(\Omega, \mathbb{S}) \times H^{\text{div}}(\Omega, \mathbb{V}), \\ F &:= L^2(\Omega) \times L^2(\Omega, \mathbb{V}) \times L^2(\Omega, \mathbb{S}) \times L^2(\Omega, \mathbb{V}), \\ F_\partial &:= L^2(\Gamma_C, \mathbb{R}^3) \times L^2(\Gamma_S, \mathbb{R}^3) \times L^2(\Gamma_F, \mathbb{R}^3). \end{aligned}$$

The set

$$D_{\mathcal{J}} = \left\{ \begin{pmatrix} \mathbf{f} \\ \mathbf{f}_\partial \\ \mathbf{e} \\ \mathbf{e}_\partial \end{pmatrix} \mid \mathbf{e} \in H, \mathbf{f} = \mathcal{J}\mathbf{e}, \mathbf{f}_\partial = \mathcal{B}_\partial \mathbf{e}, \mathbf{e}_\partial = -\mathcal{C}_\partial \mathbf{e} \right\}, \quad (5.30)$$

where $\mathbf{e} = (e_w, \mathbf{e}_\theta, \mathbf{E}_\kappa, \mathbf{e}_\gamma)$ and $\mathcal{J}, \mathcal{B}_\partial, \mathcal{C}_\partial$ are defined in (5.29), is a Stokes–Dirac structure with respect to the pairing

$$\langle \langle (\mathbf{f}^1, \mathbf{f}_\partial^1, \mathbf{e}^1, \mathbf{e}_\partial^1), (\mathbf{f}^2, \mathbf{f}_\partial^2, \mathbf{e}^2, \mathbf{e}_\partial^2) \rangle \rangle := \langle \mathbf{e}^1, \mathbf{f}^2 \rangle_F + \langle \mathbf{e}^2, \mathbf{f}^1 \rangle_F + \langle \mathbf{e}_\partial^1, \mathbf{f}_\partial^2 \rangle_{F_\partial} + \langle \mathbf{e}_\partial^2, \mathbf{f}_\partial^1 \rangle_{F_\partial}, \quad (5.31)$$

where $\mathbf{e}_\partial^i = (e_{\partial,1}^i, e_{\partial,2}^i, e_{\partial,3}^i)$, $\mathbf{f}_\partial^i = (f_{\partial,1}^i, f_{\partial,2}^i, f_{\partial,3}^i)$ and

$$\langle (\mathbf{a}, \mathbf{b}, \mathbf{c}), (\mathbf{d}, \mathbf{e}, \mathbf{f}) \rangle_{F_\partial} = \int_{\Gamma_C} \mathbf{a} \cdot \mathbf{d} \, dS + \int_{\Gamma_S} \mathbf{b} \cdot \mathbf{e} \, dS + \int_{\Gamma_F} \mathbf{c} \cdot \mathbf{f} \, dS, \quad \mathbf{a}, \mathbf{b}, \mathbf{c}, \mathbf{d}, \mathbf{e}, \mathbf{f} \in \mathbb{R}^3.$$

Crucial points and elements in favor of the conjecture Analogously to what was stated in Conjecture 1, the boundary spaces have to properly defined. If the integration by parts is carried out as in Eq. (5.26), one can follow the same lines of Conjecture 1 to support the present Conjecture.

The Mindlin plate falls within the assumption of [Skr19], hence it is a well posed boundary control pH systems.

5.2.2 Port-Hamiltonian Kirchhoff plate

Again the starting point is the Hamiltonian (total energy)

$$H = \frac{1}{2} \int_{\Omega} \left\{ \rho h \left(\frac{\partial w}{\partial t} \right)^2 + \mathbf{M} : \boldsymbol{\kappa} \right\} \, d\Omega, \quad (5.32)$$

where \mathbf{M} , $\boldsymbol{\kappa}$ are defined in Eqs. (5.10), (5.16). For what concerns the choice of the energy variables, a scalar and a tensor variable are considered:

$$\alpha_w = \rho h \frac{\partial w}{\partial t}, \quad \text{Linear momentum}, \quad \mathbf{A}_\kappa = \boldsymbol{\kappa}, \quad \text{Curvature tensor.} \quad (5.33)$$

759 The co-energy variables are found by computing the variational derivative of the Hamiltonian:

$$e_w := \frac{\delta H}{\delta \alpha_w} = \frac{\partial w}{\partial t}, \quad \text{Linear velocity}, \quad \mathbf{E}_\kappa := \frac{\delta H}{\delta \mathbf{A}_\kappa} = \mathbf{M}, \quad \text{Curvature tensor.} \quad (5.34)$$

760 The port-Hamiltonian system is then written as

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \mathbf{A}_\kappa \end{pmatrix} = \begin{bmatrix} 0 & -\text{div} \circ \text{Div} \\ \text{Grad} \circ \text{grad} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}. \quad (5.35)$$

The first equation is equivalent to (5.20). The last equation represents the fact that higher order derivatives commute

$$\begin{aligned} \partial_t \mathbf{A}_\kappa &= \text{Grad grad } e_w, \\ \partial_t \kappa &= \text{Grad grad } \partial_t w, \\ \partial_t \text{Grad grad } w &= \text{Grad grad } \partial_t w. \end{aligned}$$

761 The last equation holds for $w \in C^3(\Omega)$.

762 Theorem 3

763 *The operator $\text{Grad} \circ \text{grad}$, corresponding to the Hessian operator, is the adjoint of the double*
 764 *divergence $\text{div} \circ \text{Div}$.*

Proof. Let $\mathbb{S} = \mathbb{R}_{\text{sym}}^{d \times d}$ and consider the Hilbert space of the square integrable symmetric square tensors $L^2(\Omega, \mathbb{S})$ over an open connected set Ω (its inner product is defined in (4.12)). Consider the Hilbert space $L^2(\Omega)$ of scalar square integrable functions, endowed with the standard inner product. Consider the double divergence operator defined as:

$$\begin{aligned} \text{div Div} : L^2(\Omega, \mathbb{S}) &\rightarrow L^2(\Omega), \\ \Psi &\rightarrow \text{div Div } \Psi = \psi, \end{aligned} \quad \text{with } \psi = \text{div Div } \Psi = \sum_{i=1}^d \sum_{j=1}^d \frac{\partial^2 \Psi_{ij}}{\partial x_i \partial x_j}.$$

We shall identify div Div^*

$$\begin{aligned} \text{div Div}^* : L^2(\Omega) &\rightarrow L^2(\Omega, \mathbb{S}), \\ f &\rightarrow \text{div Div}^* f = \mathbf{F}, \end{aligned}$$

such that

$$\begin{aligned} \langle \text{div Div } \Psi, f \rangle_{L^2(\Omega)} &= \langle \Psi, \text{div Div}^* f \rangle_{L^2(\Omega, \mathbb{S})}, & \forall \Psi \in \text{Dom}(\text{div Div}) \subset L^2(\Omega, \mathbb{S}) \\ & & \forall f \in \text{Dom}(\text{div Div}^*) \subset L^2(\Omega) \end{aligned}$$

The function has to belong to the operator domain, so for instance $f \in C_0^2(\Omega) \in \text{Dom}(\text{div Div}^*)$ the space of twice differentiable scalar functions with compact support and Ψ can be chosen in the set $C_0^2(\Omega, \mathbb{S}) \in \text{Dom}(\text{div Div})$, the space of twice differentiable symmetric tensors with

compact support on Ω . A classical result is the fact that the adjoint of the vector divergence is $\operatorname{div}^* = -\operatorname{grad}$ as stated in [KZ15]. By theorem 2, it holds $\operatorname{Div}^* = -\operatorname{Grad}$. Considering that $\operatorname{div} \operatorname{Div} = \operatorname{div} \circ \operatorname{Div}$ is the composition of two different operators and that the adjoint of a composed operator is the adjoint of each operator in reverse order, i.e. $(B \circ C)^* = C^* \circ B^*$, then it can be stated

$$(\operatorname{div} \circ \operatorname{Div})^* = \operatorname{Div}^* \circ \operatorname{div}^* = \operatorname{Grad} \circ \operatorname{grad}.$$

765 Since only formal adjoints are being looked for, this concludes the proof. \square

766 The energy rate provides the boundary port variables

$$\begin{aligned} \dot{H} &= \int_{\Omega} \{ \partial_t \alpha_w e_w + \partial_t \mathbf{A}_{\kappa} : \mathbf{E}_{\kappa} \} \, d\Omega \\ &= \int_{\Omega} \{ -\operatorname{div} \operatorname{Div} \mathbf{E}_{\kappa} e_w + \operatorname{Grad} \operatorname{grad} e_w : \mathbf{E}_{\kappa} \} \, d\Omega, & \text{Stokes theorem} \\ &= \int_{\partial\Omega} \{ -\mathbf{n} \cdot \operatorname{Div} \mathbf{E}_{\kappa} e_w + (\mathbf{n} \otimes \operatorname{grad} e_w) : \mathbf{E}_{\kappa} \} \, ds, \\ &= \int_{\partial\Omega} \{ -\mathbf{n} \cdot \operatorname{Div} \mathbf{E}_{\kappa} e_w + \partial_{\mathbf{n}} e_w (\mathbf{n} \otimes \mathbf{n}) : \mathbf{E}_{\kappa} + \partial_{\mathbf{s}} e_w (\mathbf{n} \otimes \mathbf{s}) : \mathbf{E}_{\kappa} \} \, ds, & \text{Dyadic properties} \\ &= \int_{\partial\Omega} \{ \hat{q}_n w_t + \partial_{\mathbf{n}} w_t M_{nn} + \partial_{\mathbf{s}} w_t M_{ns} \} \, ds. \end{aligned} \tag{5.36}$$

767 where s is the curvilinear abscissa, $w_t := \partial_t w$ and $\partial_{\mathbf{s}} w_t$ denotes the directional derivative
768 along the tangential versor at the boundary. Additionally, the following definitions have been
769 introduced

$$\hat{q}_n := -\mathbf{n} \cdot \operatorname{Div}(\mathbf{E}_{\kappa}), \quad M_{nn} := (\mathbf{n} \otimes \mathbf{n}) : \mathbf{E}_{\kappa}, \quad M_{ns} := (\mathbf{n} \otimes \mathbf{s}) : \mathbf{E}_{\kappa}. \tag{5.37}$$

770 Variables w_t and $\partial_{\mathbf{s}} w_t$ are not independent as they are differentially related with respect to
771 derivation along \mathbf{s} (see for instance [TWK59, Chapter 4]). The tangential derivative has to be
772 moved on the torsional momentum M_{ns} . For sake of simplicity, $\partial\Omega$ is supposed to be regular.
773 Then the integration by parts provides

$$\int_{\partial\Omega} \partial_{\mathbf{s}} w_t M_{ns} \, ds = - \int_{\partial\Omega} \partial_{\mathbf{s}} M_{ns} w_t \, ds. \tag{5.38}$$

774 The final energy balance reads

$$\dot{H} = \int_{\partial\Omega} \{ w_t \tilde{q}_n + \partial_{\mathbf{n}} w_t M_{nn} \} \, ds, \tag{5.39}$$

775 where the boundary variables are

$$\begin{aligned} \text{Effective shear force} \quad \tilde{q}_n &:= \hat{q}_n - \partial_{\mathbf{s}} M_{ns}, \\ \text{Flexural momentum} \quad M_{nn} &:= \mathbf{M} : (\mathbf{n} \otimes \mathbf{n}) = \mathbf{E}_{\kappa} : (\mathbf{n} \otimes \mathbf{n}), \end{aligned} \tag{5.40}$$

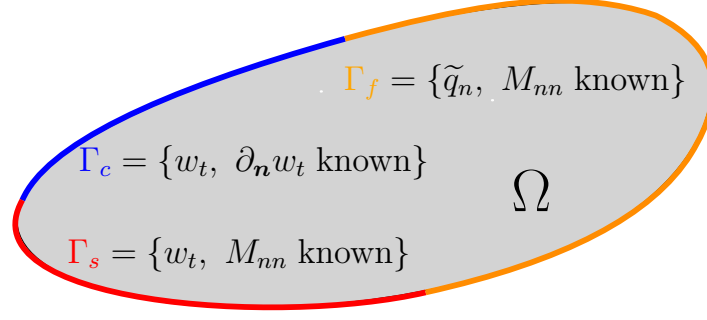


Figure 5.5: Boundary conditions for the Kirchhoff plate.

and \hat{q}_n is defined in (5.37). The corresponding power conjugated variables are:

$$\begin{aligned} \text{Vertical velocity} \quad w_t &:= \frac{\partial w}{\partial t} = e_w, \\ \text{Flexural rotation} \quad \partial_n w_t &:= \nabla e_w \cdot \mathbf{n}. \end{aligned} \tag{5.41}$$

Consider a partition of the boundary $\partial\Omega = \bar{\Gamma}_C \cup \bar{\Gamma}_S \cup \bar{\Gamma}_F$, $\Gamma_C \cap \Gamma_S \cap \Gamma_F = \{\emptyset\}$, where $\Gamma_C, \Gamma_S, \Gamma_F$ are open subset of $\partial\Omega$. Given definitions (5.40), (5.41), the boundary conditions for the Kirchhoff plate [GSV18] are the following (see Fig. 5.5):

- Clamped (C) on $\Gamma_C \subseteq \partial\Omega$: $w_t, \partial_n w_t$ known;
- Simply supported (S) on $\Gamma_S \subseteq \partial\Omega$: w_t, M_{nn} known;
- Free (F) on $\Gamma_F \subseteq \partial\Omega$: \tilde{q}_n, M_{nn} known.

Then the final pH formulation reads

$$\begin{aligned}
\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \mathbf{A}_\kappa \end{pmatrix} &= \underbrace{\begin{bmatrix} 0 & -\operatorname{div} \circ \operatorname{Div} \\ \operatorname{Grad} \circ \operatorname{grad} & \mathbf{0} \end{bmatrix}}_{\mathcal{J}} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}, \\
\mathbf{u}_\partial &= \underbrace{\begin{bmatrix} \gamma_0^{\Gamma_C} & 0 \\ \gamma_1^{\Gamma_C} & 0 \\ \gamma_0^{\Gamma_S} & 0 \\ 0 & \gamma_{nn}^{\Gamma_S} \\ 0 & \gamma_{nn,1}^{\Gamma_F} \\ 0 & \gamma_{nn}^{\Gamma_F} \end{bmatrix}}_{\mathcal{B}_\partial} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}, \\
\mathbf{y}_\partial &= \underbrace{\begin{bmatrix} 0 & \gamma_{nn,1}^{\Gamma_C} \\ 0 & \gamma_{nn}^{\Gamma_C} \\ 0 & \gamma_{nn,1}^{\Gamma_S} \\ \gamma_1^{\Gamma_S} & 0 \\ \gamma_0^{\Gamma_F} & 0 \\ \gamma_1^{\Gamma_F} & 0 \end{bmatrix}}_{\mathcal{C}_\partial} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix},
\end{aligned} \tag{5.42}$$

where $\gamma_0^{\Gamma_*} a = a|_{\Gamma_*}$ and $\gamma_1^{\Gamma_*} a = \partial_{\mathbf{n}} a|_{\Gamma_*}$ denote the standard and the normal derivative trace over the set Γ_* respectively. The symbol $\gamma_{nn,1}^{\Gamma_*}$ denotes the map $\gamma_{nn,1}^{\Gamma_*} \mathbf{A} = -\mathbf{n} \cdot \operatorname{Div} \mathbf{A} - \partial_s(\mathbf{A} : (\mathbf{n} \otimes \mathbf{s}))|_{\Gamma_*}$, while $\gamma_{nn}^{\Gamma_*} \mathbf{A} = \mathbf{A} : (\mathbf{n} \otimes \mathbf{n})|_{\Gamma_*}$ indicates the normal-normal trace of a tensor-valued function.

Remark 6

The interconnection structure \mathcal{J} in (5.42) mimics that of the Bernoulli beam [CRMPB17]. The double divergence and the Hessian coincide, in dimension one, with the second derivative.

Conjecture 3 (Stokes-Dirac structure for the Kirchhoff plate)

Consider $\mathbb{S} = \mathbb{R}_{sym}^{2 \times 2}$ and let $H^2(\Omega)$ be the space of functions with Hessian in $L^2(\Omega, \mathbb{S})$ and $H^{\operatorname{div} \operatorname{Div}}(\Omega, \mathbb{S})$ the space of vector-valued functions with double divergence in $L^2(\Omega)$. Consider the definitions

$$\begin{aligned}
H &:= H^2(\Omega) \times H^{\operatorname{div} \operatorname{Div}}(\Omega, \mathbb{S}), \\
F &:= L^2(\Omega) \times L^2(\Omega, \mathbb{S}), \\
F_\partial &:= L^2(\Gamma_C, \mathbb{R}^2) \times L^2(\Gamma_S, \mathbb{R}^2) \times L^2(\Gamma_F, \mathbb{R}^2).
\end{aligned}$$

The set

$$D_{\mathcal{J}} = \left\{ \begin{pmatrix} \mathbf{f} \\ \mathbf{f}_\partial \\ \mathbf{e} \\ \mathbf{e}_\partial \end{pmatrix} \mid \mathbf{e} \in H, \mathbf{f} = \mathcal{J}\mathbf{e}, \mathbf{f}_\partial = \mathcal{B}_\partial \mathbf{e}, \mathbf{e}_\partial = -\mathcal{C}_\partial \mathbf{e} \right\}, \tag{5.43}$$

where $\mathbf{e} = (e_w, \mathbf{E}_\kappa)$ and $\mathcal{J}, \mathcal{B}_\partial, \mathcal{C}_\partial$ are defined in (5.42), is a Stokes-Dirac structure with

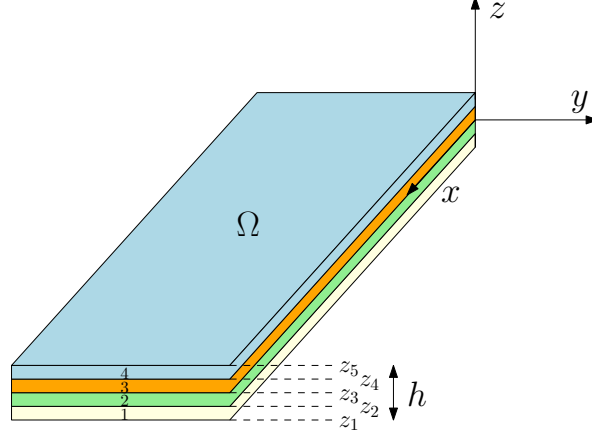


Figure 5.6: Laminated plate with 4 layers.

793 respect to the pairing

$$\langle\langle (\mathbf{f}^1, \mathbf{f}_\partial^1, \mathbf{e}^1, \mathbf{e}_\partial^1), (\mathbf{f}^2, \mathbf{f}_\partial^2, \mathbf{e}^2, \mathbf{e}_\partial^2) \rangle\rangle := \langle \mathbf{e}^1, \mathbf{f}^2 \rangle_F + \langle \mathbf{e}^2, \mathbf{f}^1 \rangle_F + \langle \mathbf{e}_\partial^1, \mathbf{f}_\partial^2 \rangle_{F_\partial} + \langle \mathbf{e}_\partial^2, \mathbf{f}_\partial^1 \rangle_{F_\partial}, \quad (5.44)$$

where $\mathbf{e}_\partial^i = (\mathbf{e}_{\partial,1}^i, \mathbf{e}_{\partial,2}^i)$, $\mathbf{f}_\partial^i = (\mathbf{f}_{\partial,1}^i, \mathbf{f}_{\partial,2}^i)$ and

$$\langle (\mathbf{a}, \mathbf{b}, \mathbf{c}), (\mathbf{d}, \mathbf{e}, \mathbf{f}) \rangle_{F_\partial} = \int_{\Gamma_C} \mathbf{a} \cdot \mathbf{d} \, dS + \int_{\Gamma_S} \mathbf{b} \cdot \mathbf{e} \, dS + \int_{\Gamma_F} \mathbf{c} \cdot \mathbf{f} \, dS, \quad \mathbf{a}, \mathbf{b}, \mathbf{c}, \mathbf{d}, \mathbf{e}, \mathbf{f} \in \mathbb{R}^2.$$

794 **Validity of the conjecture** The integration by parts has to be carried as in Eq. (5.36) to
 795 retrieve a similar discussion to the one in Conjecture 1.

796 5.3 Laminated anisotropic plates

797 Until now homogeneous isotropic materials have been considered. For this class of materials,
 798 the membrane and bending problems are decoupled. In aeronautical applications, structure
 799 are made up of laminae of different materials to enhance the mechanical properties of the
 800 resulting structure. In some cases, a certain coupling is desired, to increase the aerodynamical
 801 performance of the wing as it deforms.

802 Consider again the deformation field given by (5.1)

$$\begin{aligned} \mathbf{u}(x, y, z, t) &= \mathbf{u}^0(x, y, t) - z\boldsymbol{\theta}(x, y, t), \\ u_z(x, y, z, t) &= u_z^0(x, y, t), \end{aligned}$$

803 where $\mathbf{u} = (u_x, u_y)$. The link between in-plane deformation (5.2) and the membrane and

bending contribution (5.4), (5.5).

$$\varepsilon_{2D} = \varepsilon^0 - z\kappa \quad \text{where} \quad \varepsilon^0 = \text{Grad } \mathbf{u}^0, \quad \kappa = \text{Grad } \boldsymbol{\theta}. \quad (5.45)$$

Assume that each layer is an anisotropic material under plane stress condition. Then, it holds (see [Red03, Chapter 1] for details)

$$\boldsymbol{\Sigma}_{2D}^i = \mathcal{D}_{2D}^i \boldsymbol{\varepsilon}_{2D}^i,$$

where i indicates the layer under consideration. The matrix \mathcal{D}_{2D}^i depends on the properties of each material. To reduce the problem to bi-dimensional, the stresses have to be integrated along the thickness. Differently from isotropic plate, for laminated anisotropic plates the membrane and bending behavior are coupled. To see this consider the membrane and bending resultant of the stress

$$\mathbf{N} := \int_{-h/2}^{h/2} \boldsymbol{\Sigma}_{2D}^i \, dz, \quad \mathbf{M} := \int_{-h/2}^{h/2} -z \boldsymbol{\Sigma}_{2D}^i \, dz. \quad (5.46)$$

Since the stress are discontinuous due to the change of constitutive law along the thickness, the integration has to be performed lamina-wise. Once the computations are carried out, it is found

$$\begin{pmatrix} \mathbf{N} \\ \mathbf{M} \end{pmatrix} = \begin{bmatrix} \mathcal{D}_m & \mathcal{D}_c \\ \mathcal{D}_c & \mathcal{D}_b \end{bmatrix} \begin{pmatrix} \varepsilon^0 \\ \kappa \end{pmatrix}, \quad (5.47)$$

where

$$\mathcal{D}_m = \sum_{i=1}^{n_{\text{layer}}} \mathcal{D}_{2D}^i (z_{i+1} - z_i), \quad \mathcal{D}_c = -\frac{1}{2} \sum_{i=1}^{n_{\text{layer}}} \mathcal{D}_{2D}^i (z_{i+1}^2 - z_i^2), \quad \mathcal{D}_b = \frac{1}{3} \sum_{i=1}^{n_{\text{layer}}} \mathcal{D}_{2D}^i (z_{i+1}^3 - z_i^3), \quad (5.48)$$

and n_{layer} is the number of layers and z_i represents the height of the i^{th} layer (see Fig. 5.6). The coupling term \mathcal{D}_c disappears if a symmetric configuration is considered. For the shear contribution it is obtained

$$\mathbf{q} := \int_{-h/2}^{h/2} \boldsymbol{\sigma}_s \, dz = \mathcal{D}_s \boldsymbol{\gamma}, \quad \text{where} \quad \boldsymbol{\gamma} = \text{grad } u_z - \boldsymbol{\theta}. \quad (5.49)$$

The tensor \mathcal{D}_s is not diagonal as in the isotropic case, cf. §5.2.1.

In the following section it is shown how anisotropic laminated plates can be formulated as pHs.

5.3.1 Port-Hamiltonian laminated Mindlin plate

For a shear deformable laminated plate the kinetic and deformation energy read

$$E_{\text{kin}} = \frac{1}{2} \int_{\Omega} \left\{ \rho h \left\| \frac{\partial \mathbf{u}^0}{\partial t} \right\|^2 + \rho h \left(\frac{\partial u_z}{\partial t} \right)^2 + \frac{\rho h^3}{12} \left\| \frac{\partial \boldsymbol{\theta}}{\partial t} \right\|^2 \right\} d\Omega,$$

$$E_{\text{def}} = \frac{1}{2} \int_{\Omega} \left\{ \mathbf{N} : \boldsymbol{\varepsilon}^0 + \mathbf{M} : \boldsymbol{\kappa} + \mathbf{q} \cdot \boldsymbol{\gamma} \right\} d\Omega.$$

By using Hamilton's principle the equations of motion are retrieved (see [Red03, Chapter 3] for an exhaustive explanation)

$$\begin{aligned} \rho h \frac{\partial^2 \mathbf{u}^0}{\partial t^2} &= \text{Div } \mathbf{N}, \\ \rho h \frac{\partial^2 u_z}{\partial t^2} &= \text{div } \mathbf{q}, \\ \frac{\rho h^3}{12} \frac{\partial^2 \boldsymbol{\theta}}{\partial t^2} &= \text{Div } \mathbf{M} + \mathbf{q}, \end{aligned} \tag{5.50}$$

where \mathbf{N} , \mathbf{M} , \mathbf{q} are defined in Eqs. (5.47), (5.49). To get a port-Hamiltonian formulation, the following energy variables are chosen

$$\begin{aligned} \boldsymbol{\alpha}_u &= \rho h \frac{\partial \mathbf{u}^0}{\partial t}, & \alpha_w &= \rho h \frac{\partial u_z}{\partial t}, & \boldsymbol{\alpha}_\theta &= \frac{\rho h^3}{12} \frac{\partial \boldsymbol{\theta}}{\partial t}, \\ \mathbf{A}_{\varepsilon^0} &= \boldsymbol{\varepsilon}^0, & \mathbf{A}_\kappa &= \boldsymbol{\kappa}, & \boldsymbol{\alpha}_\gamma &= \boldsymbol{\gamma}. \end{aligned} \tag{5.51}$$

This choice highlights the nature of the problem in which the membrane part (equivalent to a 2D elasticity problem) and the bending part interact. The total energy $H = E_{\text{kin}} + E_{\text{def}}$ is now a quadratic function of the energy variables

$$E_{\text{kin}} = \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\rho h} \left\| \frac{\partial \boldsymbol{\alpha}_u}{\partial t} \right\|^2 + \frac{1}{\rho h} \left(\frac{\partial \alpha_w}{\partial t} \right)^2 + \frac{12}{\rho h^3} \left\| \frac{\partial \boldsymbol{\alpha}_\theta}{\partial t} \right\|^2 \right\} d\Omega,$$

$$E_{\text{def}} = \frac{1}{2} \int_{\Omega} \left\{ (\mathcal{D}_m \mathbf{A}_{\varepsilon^0} + \mathcal{D}_c \mathbf{A}_\kappa) : \mathbf{A}_{\varepsilon^0} + (\mathcal{D}_c \mathbf{A}_{\varepsilon^0} + \mathcal{D}_b \mathbf{A}_\kappa) : \mathbf{A}_\kappa + (\mathcal{D}_s \boldsymbol{\alpha}_\gamma) \cdot \boldsymbol{\alpha}_\gamma \right\} d\Omega,$$

The co-energies are equal to

$$\begin{aligned} e_w &:= \frac{\delta H}{\delta \boldsymbol{\alpha}_u} = \frac{\partial \mathbf{u}^0}{\partial t}, & e_w &:= \frac{\delta H}{\delta \alpha_w} = \frac{\partial u_z}{\partial t}, & e_\theta &:= \frac{\delta H}{\delta \boldsymbol{\alpha}_\theta} = \frac{\partial \boldsymbol{\theta}}{\partial t}, \\ \mathbf{E}_\kappa &:= \frac{\delta H}{\delta \mathbf{A}_{\varepsilon^0}} = \mathbf{N}, & \mathbf{E}_\kappa &:= \frac{\delta H}{\delta \mathbf{A}_\kappa} = \mathbf{M}, & e_\gamma &:= \frac{\delta H}{\delta \boldsymbol{\alpha}_\gamma} = \mathbf{q} \end{aligned} \tag{5.52}$$

The final pH formulation is found as usual considering the dynamics (5.50) and Clairaut's theorem

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_u \\ \alpha_w \\ \alpha_\theta \\ \mathbf{A}_{\varepsilon^0} \\ \mathbf{A}_\kappa \\ \alpha_\gamma \end{pmatrix} = \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{0} & \mathbf{0} \\ 0 & 0 & 0 & 0 & 0 & \text{div} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{I}_{2 \times 2} \\ \text{Grad} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \text{Grad} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \text{grad} & -\mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_u \\ e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_{\varepsilon^0} \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}. \quad (5.53)$$

The coupling between the membrane and bending part is clear when considering the link between energy and co-energy variables

$$\begin{pmatrix} \mathbf{e}_u \\ e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_{\varepsilon^0} \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix} = \begin{bmatrix} \frac{1}{\rho h} \mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ 0 & \frac{1}{\rho h} & 0 & 0 & 0 & 0 \\ \mathbf{0} & \mathbf{0} & \frac{12}{\rho h^3} \mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathcal{D}_m & \mathcal{D}_c & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathcal{D}_c & \mathcal{D}_b & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathcal{D}_s \end{bmatrix} \begin{pmatrix} \alpha_u \\ \alpha_w \\ \alpha_\theta \\ \mathbf{A}_{\varepsilon^0} \\ \mathbf{A}_\kappa \\ \alpha_\gamma \end{pmatrix}. \quad (5.54)$$

Again appropriate boundary variables and a suitable Stokes-Dirac structure can be found for this model. The final formulation is just a superposition of systems (4.16) and (5.29).

5.3.2 Port-Hamiltonian laminated Kirchhoff plate

According to the Kirchhoff hypotheses the kinetic and deformation energies reduce to

$$E_{\text{kin}} = \frac{1}{2} \int_{\Omega} \left\{ \rho h \left\| \frac{\partial \mathbf{u}^0}{\partial t} \right\|^2 + \rho h \left(\frac{\partial u_z}{\partial t} \right)^2 \right\} d\Omega,$$

$$E_{\text{def}} = \frac{1}{2} \int_{\Omega} \left\{ \mathbf{N} : \varepsilon^0 + \mathbf{M} : \kappa \right\} d\Omega,$$

where κ is defined in Eq. (5.5). Furthermore, as stated in Remark 4, the rotational contribution in the kinetic energy has been neglected. The equations of motion are (see [Red03, Chapter 3] for an exhaustive explanation)

$$\rho h \frac{\partial^2 \mathbf{u}^0}{\partial t^2} = \text{Div } \mathbf{N},$$

$$\rho h \frac{\partial^2 u_z}{\partial t^2} = -\text{div Div } \mathbf{M},$$

where \mathbf{N} , \mathbf{M} are defined in Eqs. (5.47). To get a port-Hamiltonian formulation, the following energy variables are chosen

$$\begin{aligned}\alpha_u &= \rho h \frac{\partial \mathbf{u}^0}{\partial t}, & \alpha_w &= \rho h \frac{\partial u_z}{\partial t}, \\ \mathbf{A}_{\varepsilon^0} &= \boldsymbol{\varepsilon}^0, & \mathbf{A}_\kappa &= \boldsymbol{\kappa}.\end{aligned}\tag{5.56}$$

The total energy $H = E_{\text{kin}} + E_{\text{def}}$ is now a quadratic function of the energy variables

$$\begin{aligned}E_{\text{kin}} &= \frac{1}{2} \int_{\Omega} \left\{ \frac{1}{\rho h} \left\| \frac{\partial \alpha_u}{\partial t} \right\|^2 + \frac{1}{\rho h} \left(\frac{\partial \alpha_w}{\partial t} \right)^2 \right\} d\Omega, \\ E_{\text{def}} &= \frac{1}{2} \int_{\Omega} \{ (\mathcal{D}_m \mathbf{A}_{\varepsilon^0} + \mathcal{D}_c \mathbf{A}_\kappa) : \mathbf{A}_{\varepsilon^0} + (\mathcal{D}_c \mathbf{A}_{\varepsilon^0} + \mathcal{D}_b \mathbf{A}_\kappa) : \mathbf{A}_\kappa \} d\Omega,\end{aligned}$$

The co-energies are equal to

$$\begin{aligned}e_w &:= \frac{\delta H}{\delta \alpha_w} = \frac{\partial u_z}{\partial t}, & e_u &:= \frac{\delta H}{\delta \alpha_u} = \frac{\partial \mathbf{u}^0}{\partial t}, \\ \mathbf{E}_\kappa &:= \frac{\delta H}{\delta \mathbf{A}_\kappa} = \mathbf{M}, & \mathbf{E}_{\varepsilon^0} &:= \frac{\delta H}{\delta \mathbf{A}_{\varepsilon^0}} = \mathbf{N},\end{aligned}\tag{5.57}$$

The final pH formulation is found to be

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_u \\ \alpha_w \\ \mathbf{A}_{\varepsilon^0} \\ \mathbf{A}_\kappa \end{pmatrix} = \begin{bmatrix} \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{0} \\ 0 & 0 & 0 & -\text{div} \circ \text{Div} \\ \text{Grad} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \text{Grad} \circ \text{grad} & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_u \\ e_w \\ \mathbf{E}_{\varepsilon^0} \\ \mathbf{E}_\kappa \end{pmatrix}.\tag{5.58}$$

Again, the coupling appears when considering the link between energy and co-energy variables

$$\begin{pmatrix} e_u \\ e_w \\ \mathbf{E}_{\varepsilon^0} \\ \mathbf{E}_\kappa \end{pmatrix} = \begin{bmatrix} \frac{1}{\rho h} \mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ 0 & \frac{1}{\rho h} & 0 & 0 \\ \mathbf{0} & \mathbf{0} & \mathcal{D}_m & \mathcal{D}_c \\ \mathbf{0} & \mathbf{0} & \mathcal{D}_c & \mathcal{D}_b \end{bmatrix} \begin{pmatrix} \alpha_u \\ \alpha_w \\ \mathbf{A}_{\varepsilon^0} \\ \mathbf{A}_\kappa \end{pmatrix}.\tag{5.59}$$

The energy rate provides the appropriate boundary conditions from which one can construct the Stokes-Dirac structure. The necessary computations are not performed here as the final result is just a juxtaposition of systems (4.16), (5.42).

5.4 Conclusion

In this chapter, a pH formulation for the most commonly used plate models has been detailed. Many open questions remain. In particular, how to generalize the results to shell problems, for which the domain is a surface embedded in the three dimensional space (a manifold). Computations get more involved in this case since the usage of differential geometry concepts is unavoidable. These models are important since they are widely used in the aerospace in-

dustry and ubiquitous in nature.

The reformulation of plate models using the language of differential geometry is another open research topic. Indeed, while for the Mindlin plate it should be possible to use vector-valued forms to obtain an equivalent system, for the Kirchhoff plate higher order Stokes-Dirac structure are needed [\[NY04\]](#).

Thermoelasticity in port-Hamiltonian form

Eh bien, mon ami, la terre sera un jour ce cadavre refroidi. Elle deviendra inhabitable et sera inhabitée comme la lune, qui depuis longtemps a perdu sa chaleur vitale.

Vingt mille lieues sous les mers
Jules Verne

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Thermoelasticity is the study of deformable bodies undergoing thermal excitations. It is a clear example of a multiphysics phenomenon since the heat transfer and elastic vibrations within the body mutually interact. In this chapter, a linear model of thermoelasticity is obtained under the pH formalism. Each physics is described separately and the final system is obtained considering a power-preserving interconnection of two pHs.

6.1 Port-Hamiltonian linear coupled thermoelasticity

In this section, a pH formulation of heat transfer is first introduced. The classical model of thermoelasticity is then recalled. The same model is found by interconnecting the heat equation and the linear elastodynamics problem seen as pHs. It is shown that the interconnection

preserves a quadratic functional that plays the role of a fictitious energy. The resulting system is dissipative with respect to this functional. The construction makes use of the intrinsic modularity of pHs [KZvdSB10].

6.1.1 The heat equation as a pH descriptor system

Consider the heat equation in a bounded connected set $\Omega \subset \mathbb{R}^d$, $d \in \{1, 2, 3\}$, describing the evolution of the temperature field $T(\mathbf{x}, t)$

$$\rho c_\epsilon \frac{\partial T}{\partial t} = k \Delta T + r_Q, \quad \mathbf{x} \in \Omega, \quad (6.1)$$

where ρ , c_ϵ , k , r_Q are the mass density, the specific heat density at constant strain, the thermal diffusivity and an heat source. Symbol Δ denotes the Laplacian in \mathbb{R}^d . The Dirichlet and Neumann condition of this problem are

$$\begin{aligned} T \text{ known on } \Gamma_D^T, & \quad \text{Dirichlet condition,} \\ -k \text{ grad } T \cdot \mathbf{n} \text{ known on } \Gamma_N^T, & \quad \text{Neumann condition,} \end{aligned}$$

where a partition of the boundary $\partial\Omega = \Gamma_D^T \cup \Gamma_N^T$ has been considered. This model can be put in pH form by means of a canonical interconnection structure. An algebraic relationship that describes the Fourier law has to be incorporated in the model (cf. [Kot19, Chapter 2]). Here, a differential-algebraic formulation is exploited to obtain the same system.

Let T_0 be a constant reference temperature (the introduction of this variables is instrumental for coupled thermoelasticity). The functional

$$H_T = \frac{1}{2} \int_{\Omega} \rho c_\epsilon T_0 \left(\frac{T - T_0}{T_0} \right)^2 d\Omega$$

has the physical dimension of an energy and represents a Lyapunov functional of this system. Even though it does not represent the internal energy, it has some important properties. Select as energy variable

$$\alpha_T := \rho c_\epsilon (T - T_0),$$

whose corresponding co-energy is

$$e_T := \frac{\delta H_T}{\delta \alpha_T} = \frac{\alpha_T}{\rho c_\epsilon T_0} = \frac{T - T_0}{T_0} =: \theta.$$

Introducing the heat flux $\mathbf{j}_Q := -k \text{ grad } T$ as additional variable, the heat equation (6.1) is

equivalently reformulated as

$$\begin{aligned} \begin{bmatrix} 1 & 0 \\ \mathbf{0} & \mathbf{0} \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} \alpha_T \\ \mathbf{j}_Q \end{pmatrix} &= \begin{bmatrix} 0 & -\operatorname{div} \\ -\operatorname{grad} & -(T_0 k)^{-1} \end{bmatrix} \begin{pmatrix} e_T \\ \mathbf{j}_Q \end{pmatrix} + \begin{bmatrix} 1 \\ \mathbf{0} \end{bmatrix} u_T, \\ y_T &= \begin{bmatrix} 1 & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_T \\ \mathbf{j}_Q \end{pmatrix}. \end{aligned} \quad (6.2)$$

with $u_T := r_Q$ and y_T represents the corresponding power-conjugated variable. In matrix notation, it is obtained

$$\begin{aligned} \mathcal{E}_T \partial_t \boldsymbol{\alpha}_T &= (\mathcal{J}_T - \mathcal{R}_T) \mathbf{e}_T + \mathcal{B}_T u_T, \\ y_d &= \mathcal{B}_T^* \mathbf{e}_T \end{aligned} \quad (6.3)$$

where $\boldsymbol{\alpha}_T = (\alpha_T, \mathbf{j}_Q)$, $\mathbf{e}_T = (e_T, \mathbf{j}_Q)$ and

$$\mathcal{E}_T = \begin{bmatrix} 1 & 0 \\ \mathbf{0} & \mathbf{0} \end{bmatrix}, \quad \mathcal{J}_T = \begin{bmatrix} 0 & -\operatorname{div} \\ -\operatorname{grad} & \mathbf{0} \end{bmatrix}, \quad \mathcal{R}_T = \begin{bmatrix} 0 & 0 \\ \mathbf{0} & (T_0 k)^{-1} \end{bmatrix}, \quad \mathcal{B}_T = \begin{bmatrix} 1 \\ \mathbf{0} \end{bmatrix}.$$

The system is an example of pH descriptor system (cf. [BMXZ18] for the finite dimensional case). The Hamiltonian reads

$$H_T = \frac{1}{2} \int_{\Omega} \mathbf{e}_T \cdot \mathcal{E}_T \boldsymbol{\alpha}_T \, d\Omega. \quad (6.4)$$

The power rate is then deduced

$$\begin{aligned} \dot{H}_T &= \int_{\Omega} \mathbf{e}_T \cdot \mathcal{E}_T \partial_t \boldsymbol{\alpha}_T \, d\Omega, \\ &= \int_{\Omega} \mathbf{e}_T \cdot \{(\mathcal{J}_T - \mathcal{R}_T) \mathbf{e} + \mathcal{B}_T u_T\} \, d\Omega, \\ &= \int_{\Omega} u_T y_T \, d\Omega - \int_{\Omega} \left(e_T \operatorname{div} \mathbf{j}_Q + \mathbf{j}_Q \operatorname{grad} e_T + \frac{\|\mathbf{j}_Q\|^2}{k T_0} \right) \, d\Omega, \\ &\leq \int_{\Omega} u_T y_T \, d\Omega - \int_{\partial\Omega} e_T \mathbf{j}_Q \cdot \mathbf{n} \, dS. \end{aligned} \quad (6.5)$$

This choice of Hamiltonian allows retrieving the classical boundary conditions and leads to a dissipative system. Other formulations, based on an entropy or internal energy functionals, are possible for the heat equation [DMSB09, SHM19a]. These provide an accrescent or a lossless system. Unfortunately these formulations are non linear and their discretization is a difficult task [SHM19b].

6.1.2 Classical thermoelasticity

The derivation of the classical theory of thermoelasticity is not carried out here. The reader may consult in [HE09, Chapter 1] or [Abe12, Chapter 8] for a detailed discussion on this topic.

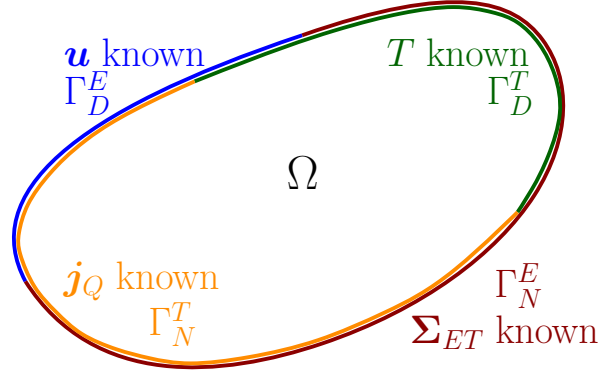


Figure 6.1: Boundary conditions for the thermoelastic problem.

914 Consider a bounded connected set $\Omega \subset \mathbb{R}^d$, $d \in \{1, 2, 3\}$. The classical equations for linear
 915 fully-coupled thermoelasticity for an isotropic thermoelastic material are [Bio56, Car73]

$$\begin{aligned}
 \rho \frac{\partial^2 \mathbf{u}}{\partial t^2} &= \text{Div}(\boldsymbol{\Sigma}_{ET}), \\
 \rho c_\epsilon \frac{\partial T}{\partial t} &= -\text{div}(\mathbf{j}_Q) - \mathcal{C}_\beta : \frac{\partial \boldsymbol{\varepsilon}}{\partial t}, \\
 \boldsymbol{\Sigma}_{ET} &= \boldsymbol{\Sigma}_E + \boldsymbol{\Sigma}_T, \\
 \boldsymbol{\Sigma}_E &= 2\mu \boldsymbol{\varepsilon} + \lambda \text{Tr}(\boldsymbol{\varepsilon}) \mathbf{I}_{d \times d}, \\
 \boldsymbol{\Sigma}_T &= -\mathcal{C}_\beta \theta, \\
 \boldsymbol{\varepsilon} &= \text{Grad}(\mathbf{u}), \\
 \mathbf{j}_Q &= -k \text{grad } T.
 \end{aligned} \tag{6.6}$$

916 For simplicity the coupling term

$$\mathcal{C}_\beta := T_0 \beta (2\mu + d\lambda) \mathbf{I}_{d \times d}$$

917 has been introduced. Field \mathbf{u} is the displacement, $\boldsymbol{\varepsilon}$ is the infinitesimal strain tensor, $\boldsymbol{\Sigma}_E, \boldsymbol{\Sigma}_T$
 918 are the stress tensor contribution due to mechanical deformation and a thermal field. Co-
 919 efficients λ, μ are the Lamé parameters, and β the thermal expansion coefficient. Given a
 920 partition of the boundary $\partial\Omega = \Gamma_D^E \cup \Gamma_N^E = \Gamma_D^T \cup \Gamma_N^T$ for the elastic and thermal domain. The
 921 general boundary conditions read (see Fig. 6.1)

$$\begin{aligned}
 \mathbf{u} \text{ known on } \Gamma_D^E \times (0, +\infty), & \quad T \text{ known on } \Gamma_D^T \times (0, +\infty), \\
 \boldsymbol{\Sigma}_{ET} \cdot \mathbf{n} \text{ known on } \Gamma_N^E \times (0, +\infty), & \quad \mathbf{j}_Q \cdot \mathbf{n} \text{ known on } \Gamma_N^T \times (0, +\infty).
 \end{aligned} \tag{6.7}$$

922 In the following section an equivalent system is constructed by interconnecting the heat
 923 equation and the elastodynamics system in a structured manner.

6.1.3 Thermoelasticity as two coupled pHs

Consider again the equation of elasticity on $\Omega \subset \mathbb{R}^d$, $d \in \{1, 2, 3\}$ (cf. Eq. (4.16)), together with a distributed input \mathbf{u}_E that plays the role of a distributed force

$$\begin{aligned} \frac{\partial}{\partial t} \begin{pmatrix} \boldsymbol{\alpha}_v \\ \mathbf{A}_\varepsilon \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \text{Div} \\ \text{Grad} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix} + \begin{bmatrix} \mathbf{I}_{d \times d} \\ \mathbf{0} \end{bmatrix} \mathbf{u}_E, \\ \mathbf{y}_E &= \begin{bmatrix} \mathbf{I}_{d \times d} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \end{pmatrix}, \end{aligned} \quad (6.8)$$

with Hamiltonian

$$H_E = \frac{1}{2} \int_{\Omega} \{ \boldsymbol{\alpha}_v \cdot \mathbf{e}_v + \mathbf{A}_\varepsilon : \mathbf{E}_\varepsilon \} \, d\Omega.$$

Recall the pH formulation of the heat equation (6.2)

$$\begin{aligned} \begin{bmatrix} 1 & 0 \\ \mathbf{0} & \mathbf{0} \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} \alpha_T \\ \mathbf{j}_Q \end{pmatrix} &= \begin{bmatrix} 0 & -\text{div} \\ -\text{grad} & -(T_0 k)^{-1} \end{bmatrix} \begin{pmatrix} e_T \\ \mathbf{j}_Q \end{pmatrix} + \begin{bmatrix} 1 \\ \mathbf{0} \end{bmatrix} u_T, \\ \mathbf{y}_T &= \begin{bmatrix} 1 & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_T \\ \mathbf{j}_Q \end{pmatrix}, \end{aligned} \quad (6.9)$$

with Hamiltonian H_T defined in (6.4). The linear thermoelastic problem can be expressed as a coupled port-Hamiltonian system. Consider the following interconnection

$$\mathbf{u}_E = -\text{Div}(\mathcal{C}_\beta \mathbf{y}_T), \quad u_T = -\mathcal{C}_\beta : \text{Grad}(\mathbf{y}_E). \quad (6.10)$$

The interconnection is power preserving as it can be compactly written as

$$\mathbf{u}_E = \mathcal{A}_\beta(\mathbf{y}_T), \quad u_T = -\mathcal{A}_\beta^*(\mathbf{y}_E).$$

where \mathcal{A}_β^* denotes the formal adjoint. The assertion is justified by the following proposition.

Proposition 5

Let $C_0^\infty(\Omega)$, $C_0^\infty(\Omega, \mathbb{R}^d)$ be the space of smooth functions and vector-valued functions respectively. Given $y_T \in C_0^\infty(\Omega)$, $\mathbf{y}_E \in C_0^\infty(\Omega, \mathbb{R}^d)$, the coupling operator

$$\begin{aligned} \mathcal{A}_\beta : C_0^\infty(\Omega) &\rightarrow C_0^\infty(\Omega, \mathbb{R}^d), \\ y_T &\rightarrow -\text{Div}(\mathcal{C}_\beta y_T) \end{aligned} \quad (6.11)$$

has formal adjoint

$$\begin{aligned} \mathcal{A}_\beta^* : C_0^\infty(\Omega, \mathbb{R}^d) &\rightarrow C_0^\infty(\Omega) \\ \mathbf{y}_E &\rightarrow -\mathcal{C}_\beta : \text{Grad}(\mathbf{y}_E) \end{aligned} \quad (6.12)$$

Proof. It is necessary to show

$$\langle \mathbf{y}_E, \mathcal{A}_\beta y_T \rangle_{L^2(\Omega, \mathbb{R}^d)} = \langle \mathcal{A}_\beta^* \mathbf{y}_E, y_T \rangle_{L^2(\Omega)}, \quad (6.13)$$

937 where for $\mathbf{u}_E, \mathbf{y}_E \in C_0^\infty(\Omega)$, $u_T, y_T \in C_0^\infty(\Omega)$

$$\langle \mathbf{u}_E, \mathbf{y}_E \rangle_{L^2(\Omega, \mathbb{R}^d)} = \int_{\Omega_E} \mathbf{u}_E \cdot \mathbf{y}_E \, d\Omega, \quad \langle u_T, y_T \rangle_{L^2(\Omega)} = \int_{\Omega_T} u_T y_T \, d\Omega. \quad (6.14)$$

938 The proof is a simple application of Theorem 5

$$\begin{aligned} \langle \mathbf{y}_E, \mathcal{A}_\beta y_T \rangle_{L^2(\Omega, \mathbb{R}^d)} &= - \int_{\Omega} \mathbf{y}_E \cdot \text{Div}(\mathcal{C}_\beta y_T) \, d\Omega, \\ &= - \int_{\Omega} \text{Grad}(\mathbf{y}_E) : \mathcal{C}_\beta y_T \, d\Omega, \\ &= \int_{\Omega} \mathcal{A}_\beta^*(\mathbf{y}_E) y_T \, d\Omega, \\ &= \langle \mathcal{A}_\beta^* \mathbf{y}_E, y_T \rangle_{L^2(\Omega)}. \end{aligned} \quad (6.15)$$

939 This concludes the proof. □

940 If the compact support assumption is removed, it is obtained

$$\begin{aligned} \langle u_T, y_T \rangle_{L^2(\Omega)} + \langle \mathbf{u}_E, \mathbf{y}_E \rangle_{L^2(\Omega, \mathbb{R}^3)} &= - \int_{\Omega} \{ (\mathcal{C}_\beta : \text{Grad} \, \mathbf{e}_v) e_T + \text{Div}(\mathcal{C}_\beta e_T) \cdot \mathbf{e}_v \} \, d\Omega, \\ &= - \int_{\Omega} \text{div}(e_T \mathcal{C}_\beta \cdot \mathbf{e}_v) \, d\Omega, \\ &= - \int_{\partial\Omega} (e_T \mathcal{C}_\beta \cdot \mathbf{n}) \cdot \mathbf{e}_v \, dS. \end{aligned} \quad (6.16)$$

Using the expression of y_T, \mathbf{y}_E , considering that T_0 is constant and applying Schwarz theorem for smooth function, the inputs are equal to

$$\mathbf{u}_E = \text{Div}(\boldsymbol{\Sigma}_T), \quad u_T = -\mathcal{C}_\beta : \text{Grad}(\mathbf{v}) = -\mathcal{C}_\beta : \frac{\partial \boldsymbol{\varepsilon}}{\partial t}.$$

941 The coupled thermoelastic problem can now be written as

$$\begin{bmatrix} \mathbf{1} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{1} & \mathbf{0} & \mathbf{0} \\ 0 & 0 & 1 & 0 \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{0} \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} \boldsymbol{\alpha}_v \\ \mathbf{A}_\varepsilon \\ \alpha_T \\ \mathbf{j}_Q \end{pmatrix} = \begin{bmatrix} \mathbf{0} & \text{Div} & \mathcal{A}_\beta & \mathbf{0} \\ \text{Grad} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ -\mathcal{A}_\beta^* & 0 & 0 & -\text{div} \\ \mathbf{0} & \mathbf{0} & -\text{grad} & -(T_0 k)^{-1} \end{bmatrix} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \\ e_T \\ \mathbf{j}_Q \end{pmatrix}, \quad (6.17)$$

with total energy given by $H = H_E + H_T$. The power balance for each subsystem is given by

$$\dot{H}_E = \int_{\Omega} \mathbf{u}_E \cdot \mathbf{y}_E \, d\Omega + \int_{\partial\Omega} \mathbf{e}_v \cdot (\mathbf{E}_\varepsilon \cdot \mathbf{n}) \, dS, \quad (6.18)$$

$$\dot{H}_T \leq \int_{\Omega} u_T y_T \, d\Omega - \int_{\partial\Omega} \theta \mathbf{j}_Q \cdot \mathbf{n} \, dS, \quad (6.19)$$

The overall power balance is easily computed considering Eqs. (6.18) (6.19) and (6.16)

$$\dot{H} = \dot{H}_E + \dot{H}_T \leq \int_{\partial\Omega} \{[\mathbf{E}_\varepsilon - e_T \mathcal{C}_\beta] \cdot \mathbf{n}\} \cdot \mathbf{e}_v \, dS - \int_{\partial\Omega} \theta \, \mathbf{j}_Q \cdot \mathbf{n} \, dS. \quad (6.20)$$

This result is the same stated in [Car73], page 332. From the power balance the classical boundary conditions are retrieved. This allows defining appropriate boundary operators for the thermoelastic problem

$$\mathbf{u}_\partial = \underbrace{\begin{bmatrix} \gamma_0^{\Gamma_D^E} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \gamma_n^{\Gamma_N^E} & -\gamma_n^{\Gamma_N^E}(\mathcal{C}_\beta \cdot) & \mathbf{0} \\ 0 & 0 & \gamma_0^{\Gamma_D^T} & 0 \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \gamma_n^{\Gamma_N^T} \end{bmatrix}}_{\mathcal{B}_\partial} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \\ e_T \\ \mathbf{j}_Q \end{pmatrix}, \quad \mathbf{y}_\partial = \underbrace{\begin{bmatrix} \mathbf{0} & \gamma_n^{\Gamma_D^E} & -\gamma_n^{\Gamma_D^E}(\mathcal{C}_\beta \cdot) & \mathbf{0} \\ \gamma_0^{\Gamma_N^E} & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & \gamma_n^{\Gamma_D^T} \\ 0 & 0 & \gamma_0^{\Gamma_N^T} & 0 \end{bmatrix}}_{\mathcal{C}_\partial} \begin{pmatrix} \mathbf{e}_v \\ \mathbf{E}_\varepsilon \\ e_T \\ \mathbf{j}_Q \end{pmatrix}. \quad (6.21)$$

System (6.17) together with (6.21) is a pH system with boundary control and observation. Indeed, the classical thermoelastic problem can be modeled as two coupled systems, demonstrating the modularity of the pH paradigm.

6.2 Thermoelastic port-Hamiltonian bending

In this section, the thermoelastic bending of thin beam and plate structures is described as coupled interconnection of pHs. Starting from classical thermoelastic models a suitable pH formulation can be obtained. This couples a mechanical system defined on a reduced domain (uni-dimensional for beams, bi-dimensional for plates), to a thermal domain defined in the three-dimensional space.

6.2.1 Thermoelastic Euler-Bernoulli beam

The model for the linear thermoelastic vibrations of an isotropic thin rod is detailed in [Cha62, LR00]. The domain of the beam is uni-dimensional $\Omega_E = \{0, L\}$, while the thermal domain is three-dimensional $\Omega_T = \{0, L\} \times S$, where S is the set representing the beam cross section. The set S is assumed to be constant along the axis for simplicity. The ruling equations are

$$\begin{aligned} \rho A \frac{\partial^2 w}{\partial t^2} &= -EI \frac{\partial^4 w}{\partial x^4} - \beta E T_0 \frac{\partial^2}{\partial x^2} \int_S z \theta \, dx \, dy, & x \in \{0, L\} &= \Omega_E, \\ \rho c_{\epsilon, B} T_0 \frac{\partial \theta}{\partial t} &= k T_0 \Delta \theta + \beta T_0 E z \frac{\partial^3 w}{\partial x^2 \partial t}, & (x, y, z) \in \Omega_E \times S &= \Omega_T, \end{aligned} \quad (6.22)$$

where $w(x, t)$ is the vertical displacement of the beam $I = \int_S z^2 \, dx \, dy$ the second moment of area, E the Young modulus and A the cross section. The constant $c_{\epsilon, B}$ is due to the thermoelastic coupling (cf. [Cha62, LR00] for a detailed explanation). The other terms have

meaning than in Section §6.1. Since the normalized temperature $\theta(x, y, z, t)$ depends on all spatial coordinates, the symbol $\Delta = \partial_{xx} + \partial_{yy} + \partial_{zz}$ is the Laplacian in three dimensions. The physical constants are assumed to be constant for simplicity.

The coupling operator is defined as

$$\mathcal{A}_{\beta,B}(y_T) := -\beta ET_0 \partial_{xx} \left(\int_S z y_T \, dx \, dy \right). \quad (6.23)$$

To unveil an interconnection that is power with respect to a certain function, the formal adjoint of the coupling operator is needed.

Proposition 6

Let $C_0^\infty(\Omega_T)$, $C_0^\infty(\Omega_E)$ be the space of smooth functions with compact support defined on Ω_T and Ω_E respectively. Given $y_T \in C_0^\infty(\Omega_T)$, $y_E \in C_0^\infty(\Omega_E)$ the formal adjoint of the coupling operator is

$$\mathcal{A}_{\beta,B}^*(y_E) = -\beta ET_0 z \partial_{xx} y_E. \quad (6.24)$$

Proof. The formal adjoint is defined by the relation

$$\langle y_E, \mathcal{A}_{\beta,B} y_T \rangle_{L^2(\Omega_E)} = \langle \mathcal{A}_{\beta,B}^* y_E, y_T \rangle_{L^2(\Omega_T)}, \quad (6.25)$$

where for $u_E, y_E \in C_0^\infty(\Omega_E)$, $u_T, y_T \in C_0^\infty(\Omega_T)$

$$\langle u_E, y_E \rangle_{L^2(\Omega_E)} = \int_{\Omega_E} u_E y_E \, dx, \quad \langle u_T, y_T \rangle_{L^2(\Omega_T)} = \int_{\Omega_T} y_T y_T \, dx \, dy \, dz. \quad (6.26)$$

Using Def. (6.23) and the integration by parts, one finds

$$\begin{aligned} \langle y_E, \mathcal{A}_{\beta,B} y_T \rangle_{L^2(\Omega_E)} &= \int_{\Omega_E} y_E \mathcal{A}_{\beta,B} y_T \, dx, \\ &= - \int_{\Omega_E} y_E \beta ET_0 \partial_{xx} \left(\int_S z y_T \, dx \, dy \right) \, dx, \\ &= - \int_{\Omega_E} (\partial_{xx} y_E) \beta ET_0 \left(\int_S z y_T \, dx \, dy \right) \, dx, \end{aligned} \quad (6.27)$$

Since $\Omega_T = \Omega_E \times S$ and from the properties of multiple integrals, it is found

$$\begin{aligned} - \int_{\Omega_E} \partial_{xx} (y_E) \beta ET_0 \left(\int_S z y_T \, dx \, dy \right) \, dx &= - \int_{\Omega_E} \int_S (\partial_{xx} y_E) \beta ET_0 z y_T \, dx \, dx \, dy, \\ &= - \int_{\Omega_T} (\partial_{xx} y_E) \beta ET_0 z y_T \, dx \, dx \, dy, \\ &= \langle \mathcal{A}_{\beta,B}^* y_E, y_T \rangle_{L^2(\Omega_T)}. \end{aligned} \quad (6.28)$$

This concludes the proof. □

979 Using Eqs. (6.23) and (6.24), System (6.22), is rewritten as

$$\begin{aligned}\rho A \frac{\partial^2 w}{\partial t^2} &= -EI \frac{\partial^4 w}{\partial x^4} + \mathcal{A}_{\beta,B} \theta, \\ \rho c_{\epsilon,B} T_0 \frac{\partial \theta}{\partial t} &= k T_0 \Delta \theta - \mathcal{A}_{\beta,B}^* \frac{\partial w}{\partial t}.\end{aligned}\quad (6.29)$$

980 Consider the Hamiltonian functional

$$H = H_E + H_T = \frac{1}{2} \int_{\Omega_E} \left\{ \rho A \left(\frac{\partial w}{\partial t} \right)^2 + EI \left(\frac{\partial^2 w}{\partial x^2} \right)^2 \right\} dx + \frac{1}{2} \int_{\Omega_T} \rho c_{\epsilon,B} T_0 \theta^2 dx dy dz. \quad (6.30)$$

981 The energy variables are chosen to make the Hamiltonian functional quadratic

$$\alpha_w = \rho A \partial_t w, \quad \alpha_\kappa = \partial_{xx} w, \quad \alpha_T = \rho c_{\epsilon,B} T_0 \theta. \quad (6.31)$$

982 The corresponding co-energy variables evaluate to

$$e_w := \frac{\delta H}{\delta \alpha_w} = \partial_t w, \quad e_\kappa := \frac{\delta H}{\delta \alpha_\kappa} = EI \partial_{xx} w, \quad e_T := \frac{\delta H}{\delta \alpha_T} = \theta. \quad (6.32)$$

983 System (6.29) can now be rewritten as

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \alpha_\kappa \\ \alpha_T \\ j_Q \end{pmatrix} = \begin{bmatrix} 0 & -\partial_{xx} & \mathcal{A}_{\beta,B} & 0 \\ \partial_{xx} & 0 & 0 & 0 \\ -\mathcal{A}_{\beta,B}^* & 0 & 0 & -\text{div} \\ 0 & 0 & -\text{grad} & -(k T_0)^{-1} \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \\ e_T \\ j_Q \end{pmatrix}, \quad (6.33)$$

984 This system is the equivalent of (6.17) for bending of beams. Hence, following the same
985 reasoning, it can be obtained starting from each subsystem in pH form by means of an
986 appropriate interconnection.

987 6.2.2 Thermoelastic Kirchhoff plate

988 For the bending of thin plate, several different models have been proposed [Cha62, Lag89,
989 Sim99, Nor06]. Here, the Chadwick model [Cha62] is considered. The thin plate occupies the
990 open connected set $\Omega_E \times \left\{ -\frac{h}{2}, \frac{h}{2} \right\}$, where h is the plate thickness. The system of equations
991 describe the midplane vertical displacement and the evolution of the temperature in the 3D
992 domain

$$\begin{aligned}\rho h \frac{\partial^2 w}{\partial t^2} &= -D_b \Delta_{2D}^2 w - \frac{\beta T_0 E}{1 - \nu} \Delta_{2D} \left(\int_{-h/2}^{h/2} z \theta dz \right), & (x, y) \in \Omega_E, \\ \rho c_{\epsilon,P} T_0 \frac{\partial \theta}{\partial t} &= -k T_0 \Delta_{3D} + \frac{\beta T_0 E z}{1 - \nu} \Delta_{2D} \left(\frac{\partial w}{\partial t} \right), & (x, y, z) \in \Omega_E \times \left\{ -\frac{h}{2}, \frac{h}{2} \right\} = \Omega_T,\end{aligned}\quad (6.34)$$

993 where $w(x, y, t)$ is the vertical deflection, $D_b = \frac{E h^3}{12(1 - \nu^2)}$ the bending rigidity (cf. Eq. (5.11)),
994 ν the Poisson modulus and $c_{\epsilon,P}$ a constant (depending on the heat capacity at constant strain

and other coupling parameters, cf. [Cha62]). Symbols $\Delta_{2D} = \partial_{xx} + \partial_{yy}$, $\Delta_{3D} = \partial_{xx} + \partial_{yy} + \partial_{zz}$ are the two- and three-dimensional Laplacian.

The coupling operator is here defined as

$$\mathcal{A}_{\beta,P}(y_T) := -\frac{\beta T_0 E}{1-\nu} \Delta_{2D} \left(\int_{-h/2}^{h/2} z y_T \, dz \right). \quad (6.35)$$

Analogously with respect to the Euler-Bernoulli beam its formal adjoint is sought for.

Proposition 7

Let $C_0^\infty(\Omega_T)$, $C_0^\infty(\Omega_E)$ be the space of smooth functions with compact support defined on Ω_T and Ω_E respectively. Given $y_T \in C_0^\infty(\Omega_T)$, $y_E \in C_0^\infty(\Omega_E)$ the formal adjoint of the coupling operator is

$$\mathcal{A}_{\beta,B}^*(y_E) = -\frac{\beta T_0 E z}{1-\nu} \Delta_{2D} y_E. \quad (6.36)$$

Proof. The proof is completely identical to Prop. 6. □

System 6.34 is rewritten as

$$\begin{aligned} \rho h \frac{\partial^2 w}{\partial t^2} &= -D_b \Delta_{2D}^2 w + \mathcal{A}_{\beta,P} \theta, \\ \rho c_{\epsilon,P} T_0 \frac{\partial \theta}{\partial t} &= -k T_0 \Delta_{3D} \theta - \mathcal{A}_{\beta,P}^* \left(\frac{\partial w}{\partial t} \right), \end{aligned} \quad (6.37)$$

The Hamiltonian functional equals

$$\begin{aligned} H = H_E + H_T &= \frac{1}{2} \int_{\Omega_E} \left\{ \rho h \left(\frac{\partial w}{\partial t} \right)^2 + (\mathcal{D}_b \text{Hess}_{2D} w) : \text{Hess}_{2D} w \right\} \, dx \, dy \\ &+ \frac{1}{2} \int_{\Omega_T} \rho c_{\epsilon,P} T_0 \theta^2 \, dx \, dy \, dz, \end{aligned} \quad (6.38)$$

where Hess_{2D} is the Hessian in two dimensions and \mathcal{D}_b was defined in (5.11) (cf. Sec. §5.1.1).

The energy and co-energy variables are

$$\begin{aligned} \alpha_w &= \rho h \partial_t w, & \mathbf{A}_\kappa &= \text{Hess}_{2D} w, & \alpha_T &= \rho c_{\epsilon,P} T_0 \theta, \\ e_w &= \partial_t w, & \mathbf{E}_\kappa &= \mathcal{D}_b \text{Hess}_{2D} w, & e_T &= \theta. \end{aligned} \quad (6.39)$$

System (6.37) is rewritten as

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \mathbf{A}_\kappa \\ \alpha_T \\ j_Q \end{pmatrix} = \begin{bmatrix} 0 & -\text{div Div}_{2D} & \mathcal{A}_{\beta,P} & 0 \\ \text{Hess}_{2D} & \mathbf{0} & \mathbf{0} & 0 \\ -\mathcal{A}_{\beta,P}^* & 0 & 0 & -\text{div}_{3D} \\ \mathbf{0} & \mathbf{0} & -\text{grad}_{3D} & -(kT_0)^{-1} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \\ e_T \\ j_Q \end{pmatrix}, \quad (6.40)$$

1010 The subscript $2D$, $3D$ refers to two- and three-dimensional operators respectively. The final
 1011 system reproduces the same structured coupling already observed for (6.17), (6.33).

1012 **Remark 7**

1013 *The thermoelastic bending can be reduced to two problems defined on the same domain (cf.*
 1014 *[HZ97] for beams and [AL00] for plates) by introducing the following approximation of the*
 1015 *temperature field*

$$\theta(x, y, z) = \theta_0 + z\theta_1, \quad (6.41)$$

1016 *where $\theta_0 = \theta_0(x)$, $\theta_1 = \theta_1(x)$ for beams and $\theta_0 = \theta_0(x, y)$, $\theta_1 = \theta_1(x, y)$ for plates. However,*
 1017 *this introducing a strong simplification as the thermal phenomena typically occur in the whole*
 1018 *three-dimensional space.*

1019 **6.3 Conclusion**

1020 In this chapter, it was shown classical linear thermoelastic problem are equivalent to two
 1021 coupled port-Hamiltonian systems. This is especially interesting for the simulation of ther-
 1022 moelastic phenomena: each subsystem can be discretized separately and then coupled to the
 1023 other using the discretized coupling operator. This allows to track easily how the energy flows
 1024 within the two physics.

1025

Part III

1026

Finite element structure preserving discretization

1027

Partitioned finite element method

Every truth is simple... is that not doubly a lie?

Twilight of the Idols
Friedrich Nietzsche

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Discretization is the process of transferring continuous models into discrete counterparts. The discrete model should be faithful to the continuous one. To this aim, it is usually essential that the main properties of the continuous system are preserved at the discrete level. An algorithm that is capable of conserving properties at the discrete level is called structure-preserving [CMKO11]. In this chapter, a method to spatially discretize infinite-dimensional pHs into finite-dimensional ones in a structure preserving manner is illustrated.

7.1 Discretization under uniform boundary condition

A discrete version of a infinite-dimensional pH system is meant to preserve the underlying properties related to power continuity. To achieve this purpose, the discretization procedure consists of two steps [KML18]:

- Finite-dimensional approximation of the Stokes-Dirac structure, i.e. the formally skew symmetric differential operator that defines the structure. The duality of the power

variables has to be mapped onto the finite approximation. The subspace of the discrete variables will be represented by a Dirac structure.

- The Hamiltonian requires as well a suitable discretization, which gives rise to a discrete Hamiltonian.

A structure-preserving discretization is able to construct an equivalent pH system that possess the structural properties of the original model:

Infinite dimensional pH system	Structure-preserving discretization
<p>PDE with distributed inputs:</p> $\frac{\partial \alpha}{\partial t}(\mathbf{x}, t) = \mathcal{J} \frac{\delta H}{\delta \alpha} + \mathcal{B} \mathbf{u}_{\Omega}(\mathbf{x}, t),$ $\mathbf{y}_{\Omega}(\mathbf{x}, t) = \mathcal{B}^* \frac{\delta H}{\delta \alpha}.$ <p>Boundary conditions:</p> $\mathbf{u}_{\partial} = \mathcal{B}_{\partial} \frac{\delta H}{\delta \alpha}, \quad \mathbf{y}_{\partial} = \mathcal{C}_{\partial} \frac{\delta H}{\delta \alpha}.$ <p>Power balance (Stokes Theorem):</p> $\dot{H} = \int_{\partial\Omega} \mathbf{u}_{\partial} \cdot \mathbf{y}_{\partial} \, dS + \int_{\Omega} \mathbf{u}_{\Omega} \cdot \mathbf{y}_{\Omega} \, d\Omega.$	<p>Resulting ODE:</p> $\dot{\alpha}_d = \mathbf{J} \nabla H_d + \mathbf{B}_{\Omega} \mathbf{u}_{\Omega} + \mathbf{B}_{\partial} \mathbf{u}_{\partial},$ $\mathbf{y}_{\Omega} = \mathbf{B}_{\Omega}^{\top} \nabla H_d,$ $\mathbf{y}_{\partial} = \mathbf{B}_{\partial}^{\top} \nabla H_d.$ <p>Discretized Hamiltonian:</p> $H_d := H(\alpha \equiv \alpha_d).$ <p>Power balance:</p> $\dot{H} = \mathbf{u}_{\partial}^{\top} \mathbf{y}_{\partial} + \mathbf{u}_{\Omega}^{\top} \mathbf{y}_{\Omega}.$

In this thesis the Partitioned Finite Element Method (PFEM), originally presented in [CRML18, CRML19], is chosen to obtain discretized models of dpHs. This procedure boils down to three simple steps

1. The system is written in weak form;
2. An integration by parts is applied to highlight the appropriate boundary control;
3. A Galerkin method is employed to obtain a finite-dimensional system. For the approximation basis the finite element method is here employed but spectral methods can be used as well.

Once the system has been put into weak form, a subset of the equations is integrated by parts, so that boundary variables are naturally included into the formulation and appear as control inputs, the collocated outputs being defined accordingly. The discretization of energy and co-energy variables (and the associated test functions) leads directly to a full rank representation for the finite-dimensional pH system. This approach makes possible the usage of FEM software, like FEniCS [LMW⁺12], or Firedrake [RHM⁺17]. The procedure is universal, as it relies on a general integration by parts formula that characterizes multi-dimensional pHs. This is why the methodology is illustrated in all its generality and then detailed for

some particular examples.

This methodology is easily applicable under a uniform causality assumption. The case of mixed boundary conditions requires additional care and will be treated in the subsequent Section §7.2.

7.1.1 General procedure

Given an open connected set $\Omega \in \mathbb{R}^d$, $d \in \{1, 2, 3\}$, consider a generic pH system defined on Ω

$$\partial_t \alpha = \mathcal{J}e, \quad \alpha \in L^2(\Omega, \mathbb{F}), \quad \mathcal{J} : L^2(\Omega, \mathbb{F}) \rightarrow L^2(\Omega, \mathbb{F}) \mid \mathcal{J} = -\mathcal{J}^*, \quad (7.1a)$$

$$e := \delta_\alpha H, \quad e \in H^\mathcal{J} := \left\{ e \in L^2(\Omega, \mathbb{F}) \mid \mathcal{J}e \in L^2(\Omega, \mathbb{F}) \right\}, \quad (7.1b)$$

$$u_\partial = \mathcal{B}_\partial e, \quad u_\partial \in \mathbb{R}^m, \quad (7.1c)$$

$$y_\partial = \mathcal{C}_\partial e, \quad y_\partial \in \mathbb{R}^m. \quad (7.1d)$$

The operator $\mathcal{J} : L^2(\Omega, \mathbb{F}) \rightarrow L^2(\Omega, \mathbb{F})$ is a differential, formally skew adjoint operator $\mathcal{J} = -\mathcal{J}^*$ over the space $L^2(\Omega, \mathbb{F})$. The set \mathbb{F} is an appropriate Cartesian product of either scalar, vectorial or tensorial quantities. Its precise definition depends on the example upon consideration. For scalars $(a, b) \in L^2(\Omega)$, vectors $(\mathbf{a}, \mathbf{b}) \in L^2(\Omega, \mathbb{R}^d)$ and tensors $(\mathbf{A}, \mathbf{B}) \in L^2(\Omega, \mathbb{R}^{d \times d})$ the L^2 inner product is given by

$$\langle a, b \rangle_{L^2(\Omega)} = \int_\Omega ab \, d\Omega, \quad \langle \mathbf{a}, \mathbf{b} \rangle_{L^2(\Omega, \mathbb{R}^d)} = \int_\Omega \mathbf{a} \cdot \mathbf{b} \, d\Omega, \quad \langle \mathbf{A}, \mathbf{B} \rangle_{L^2(\Omega, \mathbb{R}^{d \times d})} = \int_\Omega \mathbf{A} : \mathbf{B} \, d\Omega. \quad (7.2)$$

For scalars $a_\partial, b_\partial \in L^2(\partial\Omega)$ and vectors $\mathbf{a}_\partial, \mathbf{b}_\partial \in L^2(\partial\Omega, \mathbb{R}^m)$ defined on the boundary the inner product is defined as

$$\langle a_\partial, b_\partial \rangle_{L^2(\partial\Omega)} = \int_{\partial\Omega} a_\partial b_\partial \, dS, \quad \langle \mathbf{a}_\partial, \mathbf{b}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} = \int_{\partial\Omega} \mathbf{a}_\partial \cdot \mathbf{b}_\partial \, dS. \quad (7.3)$$

The Hamiltonian functional of Eq. (7.1b) is allowed to be non linear in the energy variables

$$H = \int_\Omega \mathcal{H}(\alpha) \, d\Omega,$$

where $\mathcal{H}(\alpha) : L^2(\Omega, \mathbb{F}) \rightarrow \mathbb{R}$ is a non linear function.

To applied this methodology the non linearities are restricted to the Hamiltonian and a uniform causality condition is supposed to characterize the system. It is required as well that the system admits a partition of the variables. This requirement is always encounter in the following examples. These hypotheses are resumed in the following assumptions.

Assumption 2 (Partitioning of the system)

1101 Consider system (7.1a). It is assumed that the Hilbert space $L^2(\Omega, \mathbb{F}) := L^2(\Omega, \mathbb{F})$ admits the
 1102 splitting $L^2(\Omega, \mathbb{F}) = L^2(\Omega, \mathbb{A}) \times L^2(\Omega, \mathbb{B})$. This means that $\mathbb{F} = \mathbb{A} \times \mathbb{B}$.
 1103

1104 The operator \mathcal{J} is assumed to be skew-symmetric (or formally skew-adjoint) on $L^2(\Omega, \mathbb{F})$
 1105 and linear:

$$\mathcal{J} = \mathcal{J}_a + \mathcal{J}_d, \quad (7.4)$$

1106 where \mathcal{J}_a is the algebraic contribution (a skew-symmetric matrix) and \mathcal{J}_d the differential
 1107 contribution. The algebraic part is assumed to take the form

$$\mathcal{J}_a = \begin{bmatrix} 0 & -\mathbf{L}^\top \\ \mathbf{L} & 0 \end{bmatrix}, \quad \begin{array}{l} \mathbf{L}^\top : L^2(\Omega, \mathbb{B}) \rightarrow L^2(\Omega, \mathbb{A}), \\ \mathbf{L} : L^2(\Omega, \mathbb{A}) \rightarrow L^2(\Omega, \mathbb{B}), \end{array} \quad (7.5)$$

1108 where \mathbf{L} is a bounded operator. Analogously, the linear differential operator \mathcal{J}_d is assumed to
 1109 be of the form

$$\mathcal{J}_d = \begin{bmatrix} 0 & -\mathcal{L}^* \\ \mathcal{L} & 0 \end{bmatrix}, \quad \begin{array}{l} \mathcal{L}^* : L^2(\Omega, \mathbb{B}) \rightarrow L^2(\Omega, \mathbb{A}), \\ \mathcal{L} : L^2(\Omega, \mathbb{A}) \rightarrow L^2(\Omega, \mathbb{B}), \end{array} \quad (7.6)$$

1110 where \mathcal{L}^* denotes the formal adjoint of the linear differential operator \mathcal{L} . The operator \mathcal{L} is
 1111 unbounded and can be either a first or a second order differential operator (in the latter case
 1112 it can be expressed as $\mathcal{L} = \mathcal{L}_1 \circ \mathcal{L}_2$). Given the splitting $L^2(\Omega, \mathbb{A}) \times L^2(\Omega, \mathbb{B}) = L^2(\Omega, \mathbb{F})$ the
 1113 Hilbert space $H^\mathcal{J}$ can be split as well as

$$H^\mathcal{J} = H^\mathcal{L} \times H^{-\mathcal{L}^*}, \quad \begin{array}{l} H^\mathcal{L} := \{ \mathbf{u}_1 \in L^2(\Omega, \mathbb{A}) \mid \mathcal{L}\mathbf{u}_1 \in L^2(\Omega, \mathbb{B}) \}, \\ H^{-\mathcal{L}^*} := \{ \mathbf{u}_2 \in L^2(\Omega, \mathbb{B}) \mid -\mathcal{L}^*\mathbf{u}_2 \in L^2(\Omega, \mathbb{A}) \} \end{array} \quad (7.7)$$

1114 The boundary operators are then supposed to fulfill the following assumption, that guar-
 1115 antees a uniform causality condition.

1116 **Assumption 3** (General integration by parts formula)

1117 Assume that there exist two boundary operators $\mathcal{N}_{\partial,1}$, $\mathcal{N}_{\partial,2}$ such that for $(\mathbf{u}_1, \mathbf{u}_2) \in H^\mathcal{L} \times H^{-\mathcal{L}^*}$
 1118 a general integration by parts formula holds

$$\langle \mathbf{u}_2, \mathcal{L}\mathbf{u}_1 \rangle_{L^2(\Omega, \mathbb{B})} - \langle \mathcal{L}^*\mathbf{u}_2, \mathbf{u}_1 \rangle_{L^2(\Omega, \mathbb{A})} = \langle \mathcal{N}_{\partial,1}\mathbf{u}_1, \mathcal{N}_{\partial,2}\mathbf{u}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \quad (7.8)$$

1119 The boundary operators $\mathcal{B}_\partial, \mathcal{C}_\partial$ of Eqs. (7.1c), (7.1d), are then assumed to verify, in an
 1120 exclusive manner, either

$$\mathcal{B}_\partial = \begin{bmatrix} 0 & \mathcal{N}_{\partial,2} \end{bmatrix}, \quad \mathcal{C}_\partial = \begin{bmatrix} \mathcal{N}_{\partial,1} & 0 \end{bmatrix}, \quad (7.9)$$

1121 or

$$\mathcal{B}_\partial = \begin{bmatrix} \mathcal{N}_{\partial,1} & 0 \end{bmatrix}, \quad \mathcal{C}_\partial = \begin{bmatrix} 0 & \mathcal{N}_{\partial,2} \end{bmatrix}. \quad (7.10)$$

1122 **Remark 8** (Duality pairing for rigged Hilbert spaces)

1123 The integration by part formula establishes a duality pairing between Sobolev spaces. This

duality pairing is then compatible with an L^2 inner product in presence of a rigged Hilbert space (Gelfand triple). Without entering into technical details, we shall always use this equivalence of representation. Therefore, the boundary integrals are expressed as L^2 inner product over the boundary.

Thanks to Assumption 2, System (7.1) is rewritten as

$$\partial_t \begin{pmatrix} \alpha_1 \\ \alpha_2 \end{pmatrix} = \begin{bmatrix} 0 & -\mathbf{L}^\top - \mathcal{L}^* \\ \mathbf{L} + \mathcal{L} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{aligned} \alpha_1 &\in L^2(\Omega, \mathbb{A}), \\ \alpha_2 &\in L^2(\Omega, \mathbb{B}), \end{aligned} \quad (7.11a)$$

$$\begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} := \begin{pmatrix} \delta_{\alpha_1} H \\ \delta_{\alpha_2} H \end{pmatrix}, \quad \begin{aligned} \mathbf{e}_1 &\in H^\mathcal{L}, \\ \mathbf{e}_2 &\in H^{-\mathcal{L}^*}. \end{aligned} \quad (7.11b)$$

In light of Assumption 3, if Eq. (7.9) holds the boundary variables are given by

$$\mathbf{u}_\partial = \mathcal{N}_2 \mathbf{e}_2, \quad \mathbf{y}_\partial = \mathcal{N}_1 \mathbf{e}_1, \quad \mathbf{u}_\partial, \mathbf{y}_\partial \in \mathbb{R}^m. \quad (7.12)$$

Otherwise, if Eq. (7.10) applies, then

$$\mathbf{u}_\partial = \mathcal{N}_1 \mathbf{e}_1, \quad \mathbf{y}_\partial = \mathcal{N}_2 \mathbf{e}_2, \quad \mathbf{u}_\partial, \mathbf{y}_\partial \in \mathbb{R}^m. \quad (7.13)$$

In both cases, the power balance reads

$$\begin{aligned} \dot{H} &= \langle \mathbf{e}_1, \partial_t \alpha_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathbf{e}_2, \partial_t \alpha_2 \rangle_{L^2(\Omega, \mathbb{B})}, \\ &= \langle \mathbf{e}_1, -\mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathbf{e}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \\ &= \langle \mathcal{N}_{\partial,1} \mathbf{e}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &= \langle \mathbf{y}_\partial, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \quad (7.14)$$

We are now in a position to illustrate the methodology.

Step 1 First consider the weak form of system (7.11a), obtained by taking the L^2 inner product introducing an appropriate test function $\mathbf{v} = (\mathbf{v}_1, \mathbf{v}_2) \in \mathbb{A} \times \mathbb{B} = \mathbb{F}$ and integrating over the domain Ω

$$\begin{aligned} \langle \mathbf{v}_1, \partial_t \alpha_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}, \\ \langle \mathbf{v}_2, \partial_t \alpha_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}. \end{aligned} \quad (7.15)$$

To obtain a closed system, the constitutive law (7.11b) and the output variables (7.1d) are put in weak form

$$\begin{aligned} \langle \mathbf{v}_1, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= \langle \mathbf{v}_1, \delta_{\alpha_1} H \rangle_{L^2(\Omega, \mathbb{A})}, \\ \langle \mathbf{v}_2, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \delta_{\alpha_2} H \rangle_{L^2(\Omega, \mathbb{B})}, \\ \langle \mathbf{v}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathbf{v}_\partial, \mathcal{C}_\partial \mathbf{e} \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \end{aligned} \quad (7.16)$$

where the test function $\mathbf{v}_\partial \in L^2(\partial\Omega, \mathbb{R}^m)$ is defined on the boundary $\partial\Omega$ and \mathcal{C}_∂ is defined either by Eq. (7.9) or (7.10).

Step 2 Next the integration by part has to be carried out. The choice is dictated by the boundary control to be imposed on the system. Consider again Eq. (7.15). The integration by parts can be carried out either on term $-\langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}$, or on term $\langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}$. Depending on which line undergoes the integration by parts (this is why the name Partitioned Finite Element method), two structure preserving weak forms are obtained. These differ by the boundary causality imposed to the system.

Integration by parts of the term $-\langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}$ In this case case, using Eq. (7.8), it is obtained

$$-\langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} = -\langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \quad (7.17)$$

Then the weak form of the system dynamics reads

$$\begin{aligned} \langle \mathbf{v}_1, \partial_t \boldsymbol{\alpha}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ \langle \mathbf{v}_2, \partial_t \boldsymbol{\alpha}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \end{aligned} \quad (7.18)$$

The following proposition is crucial as the lossless character of the infinite-dimensional system (due to the formally skew-adjoint operator) translates into an equivalent property for the corresponding bilinear form in the weak form.

Proposition 8

Given the Hilbert space $H_2^\mathcal{L} := H^\mathcal{L} \times L^2(\Omega, \mathbb{B})$ and variables $\mathbf{v} = (\mathbf{v}_1, \mathbf{v}_2) \in H_2^\mathcal{L}$, $\mathbf{e} = (\mathbf{e}_1, \mathbf{e}_2) \in H_2^\mathcal{L}$, the bilinear form

$$\begin{aligned} j_\mathcal{L} : H_2^\mathcal{L} \times H_2^\mathcal{L} &\longrightarrow \mathbb{R}, \\ (\mathbf{v}, \mathbf{e}) &\longrightarrow -\langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} \end{aligned}$$

is skew-symmetric.

Proof. The proof is obtained by the following computation

$$\begin{aligned} j_\mathcal{L}(\mathbf{v}, \mathbf{e}) &= -\langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \\ &= -\left(-\langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} \right), \\ &= -\left(-\langle \mathcal{L} \mathbf{e}_1, \mathbf{v}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{e}_2, \mathcal{L} \mathbf{v}_1 \rangle_{L^2(\Omega, \mathbb{B})} \right) = -j_\mathcal{L}(\mathbf{e}, \mathbf{v}). \end{aligned}$$

□

Now assume that the system satisfies the boundary causality condition 7.12. Then, this

choice of the integration by parts lead to the following weak formulation

$$\begin{aligned}
\langle \mathbf{v}_1, \partial_t \boldsymbol{\alpha}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
\langle \mathbf{v}_2, \partial_t \boldsymbol{\alpha}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \\
\langle \mathbf{v}_1, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= \langle \mathbf{v}_1, \delta_{\alpha_1} H \rangle_{L^2(\Omega, \mathbb{A})}, \\
\langle \mathbf{v}_2, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \delta_{\alpha_2} H \rangle_{L^2(\Omega, \mathbb{B})}, \\
\langle \mathbf{v}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathbf{v}_\partial, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}.
\end{aligned} \tag{7.19}$$

Integration by parts of the term $\langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}$ Using Eq. (7.8), it is obtained

$$\langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} = \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \tag{7.20}$$

Then the weak form of the system dynamics reads

$$\begin{aligned}
\langle \mathbf{v}_1, \partial_t \boldsymbol{\alpha}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}, \\
\langle \mathbf{v}_2, \partial_t \boldsymbol{\alpha}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)},
\end{aligned} \tag{7.21}$$

Again the bilinear form arising from the formally skew-adjoint operator is skew-symmetric.

Proposition 9

Given the Hilbert space $H_1^{-\mathcal{L}^*} = L^2(\Omega, \mathbb{A}) \times H^{-\mathcal{L}^*}$ and variables $\mathbf{v} = (\mathbf{v}_1, \mathbf{v}_2) \in H_1^{-\mathcal{L}^*}$, $\mathbf{e} = (\mathbf{e}_1, \mathbf{e}_2) \in H_1^{-\mathcal{L}^*}$, the bilinear form

$$\begin{aligned}
j_{-\mathcal{L}^*} : H_1^{-\mathcal{L}^*} \times H_1^{-\mathcal{L}^*} &\longrightarrow \mathbb{R}, \\
(\mathbf{v}, \mathbf{e}) &\longrightarrow -\langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})}
\end{aligned}$$

is skew-symmetric.

Proof. The proof follows from the computation

$$\begin{aligned}
j_{-\mathcal{L}^*}(\mathbf{v}, \mathbf{e}) &= -\langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})}, \\
&= -\left(-\langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} \right), \\
&= -\left(-\langle \mathbf{e}_1, \mathcal{L}^* \mathbf{v}_2 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{L}^* \mathbf{e}_2, \mathbf{v}_1 \rangle_{L^2(\Omega, \mathbb{A})} \right) = -j_{-\mathcal{L}^*}(\mathbf{e}, \mathbf{v}).
\end{aligned}$$

□

Now assume that the system satisfies the boundary causality condition (7.13). Then, the

1161 final weak formulation reads

$$\begin{aligned}
\langle \mathbf{v}_1, \partial_t \boldsymbol{\alpha}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}, \\
\langle \mathbf{v}_2, \partial_t \boldsymbol{\alpha}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{N}_{\partial, 2} \mathbf{v}_2, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
\langle \mathbf{v}_1, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= \langle \mathbf{v}_1, \delta_{\alpha_1} H \rangle_{L^2(\Omega, \mathbb{A})}, \\
\langle \mathbf{v}_2, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \delta_{\alpha_2} H \rangle_{L^2(\Omega, \mathbb{B})}, \\
\langle \mathbf{v}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathbf{v}_\partial, \mathcal{N}_{\partial, 2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}.
\end{aligned} \tag{7.22}$$

1162 **Galerkin discretization** To conclude the illustration of this methodology, a Galerkin dis-
 1163 cretization is introduced. This means that test, energy and co-energy functions are discretized
 1164 using the same basis. Furthermore the boundary variables are discretized as well using bases
 1165 defined over the boundary

$$\begin{aligned}
\mathbf{v}_1 &\approx \sum_{i=1}^{n_1} \phi_1^i(\mathbf{x}) v_1^i, & \boldsymbol{\alpha}_1 &\approx \sum_{i=1}^{n_1} \phi_1^i(\mathbf{x}) \alpha_1^i(t), & \mathbf{e}_1 &\approx \sum_{i=1}^{n_1} \phi_1^i(\mathbf{x}) e_1^i(t), & \mathbf{x} &\in \Omega, \\
\mathbf{v}_2 &\approx \sum_{i=1}^{n_2} \phi_2^i(\mathbf{x}) v_2^i, & \boldsymbol{\alpha}_2 &\approx \sum_{i=1}^{n_2} \phi_2^i(\mathbf{x}) \alpha_2^i(t), & \mathbf{e}_2 &\approx \sum_{i=1}^{n_2} \phi_2^i(\mathbf{x}) e_2^i(t), & \mathbf{x} &\in \Omega, \\
\mathbf{v}_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(\mathbf{s}) v_\partial^i, & \mathbf{u}_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(\mathbf{s}) u_\partial^i(t), & \mathbf{y}_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(\mathbf{s}) y_\partial^i(t), & \mathbf{s} &\in \partial\Omega,
\end{aligned} \tag{7.23}$$

1166 where $\phi_1^i \in \mathbb{A}$, $\phi_2^i \in \mathbb{B}$, $\phi_\partial^i \in \mathbb{R}^m$.

1167 **Discretization of the weak form (7.19)** Plugging the approximation into the weak
 1168 form (7.19) and consider that the resulting equation holds $\forall v_1^i, v_2^j, v_\partial^k$ ($i \in \{1, n_1\}$, $j \in$
 1169 $\{1, n_2\}$, $k \in \{1, n_\partial\}$), the finite dimensional system is obtained

$$\begin{aligned}
\begin{bmatrix} \mathbf{M}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_2 \end{bmatrix} \begin{pmatrix} \dot{\boldsymbol{\alpha}}_{d,1} \\ \dot{\boldsymbol{\alpha}}_{d,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top - \mathbf{D}_\mathcal{L}^\top \\ \mathbf{D}_0 + \mathbf{D}_\mathcal{L} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} + \begin{bmatrix} \mathbf{B}_1 \\ \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\
\begin{bmatrix} \mathbf{M}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_2 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} &= \begin{bmatrix} \partial_{\alpha_{d,1}} H_d(\boldsymbol{\alpha}_d) \\ \partial_{\alpha_{d,2}} H_d(\boldsymbol{\alpha}_d) \end{bmatrix}, \\
\mathbf{M}_{\partial} \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{B}_1^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}.
\end{aligned} \tag{7.24}$$

1170 Vectors $\boldsymbol{\alpha}_{d,1}$, $\boldsymbol{\alpha}_{d,2}$, \mathbf{e}_1 , \mathbf{e}_2 , \mathbf{u}_∂ , \mathbf{y}_∂ are given by the column-wise concatenation of their respec-
 1171 tive degrees of freedom. The matrices are defined as follows

$$\begin{aligned}
M_1^{ij} &= \langle \phi_1^i, \phi_1^j \rangle_{L^2(\Omega, \mathbb{A})}, & D_0^{mi} &= \langle \phi_2^m, \mathbf{L} \phi_1^i \rangle_{L^2(\Omega, \mathbb{B})}, & B_1^{ik} &= \langle \mathcal{N}_{\partial, 1} \phi_1^i, \phi_\partial^k \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\
M_2^{mn} &= \langle \phi_2^m, \phi_2^n \rangle_{L^2(\Omega, \mathbb{B})}, & D_\mathcal{L}^{mi} &= \langle \phi_2^m, \mathcal{L} \phi_1^i \rangle_{L^2(\Omega, \mathbb{B})}, & M_\partial^{lk} &= \langle \phi_\partial^l, \phi_\partial^k \rangle_{L^2(\partial\Omega, \mathbb{R}^m)},
\end{aligned} \tag{7.25}$$

where $i, j \in \{1, n_1\}$, $m, n \in \{1, n_2\}$, $l, k \in \{1, n_\partial\}$. Introducing the definitions

$$\begin{aligned}\delta_{\alpha_{d,1}} H_d &:= \delta_{\alpha_1} H \left(\alpha_1 = \sum_{i=1}^{n_1} \phi_1^i \alpha_1^i, \alpha_2 = \sum_{i=1}^{n_1} \phi_2^i \alpha_2^i \right), \\ \delta_{\alpha_{d,2}} H_d &:= \delta_{\alpha_2} H \left(\alpha_1 = \sum_{i=1}^{n_1} \phi_1^i \alpha_1^i, \alpha_2 = \sum_{i=1}^{n_1} \phi_2^i \alpha_2^i \right),\end{aligned}$$

the discretized gradient of the Hamiltonian read

$$\begin{aligned}\partial_{\alpha_{d,1}^i} H_d(\alpha_d) &= \left\langle \phi_1^i, \delta_{\alpha_{d,1}} H_d \right\rangle_{L^2(\Omega, \mathbb{A})}, \quad i \in \{1, n_1\}, \\ \partial_{\alpha_{d,2}^j} H_d(\alpha_d) &= \left\langle \phi_2^j, \delta_{\alpha_{d,2}} H_d \right\rangle_{L^2(\Omega, \mathbb{B})}, \quad j \in \{1, n_2\}.\end{aligned}\tag{7.26}$$

A pH system in canonical form is found observing that Sys. (7.24) is compactly rewritten as

$$\mathbf{M} \dot{\alpha}_d = \mathbf{J}_{\mathcal{L}} \mathbf{e} + \mathbf{B} \mathbf{u}_\partial, \tag{7.27}$$

$$\mathbf{M} \mathbf{e} = \nabla H_d(\alpha_d), \tag{7.28}$$

$$\mathbf{M}_\partial \mathbf{y}_\partial = \mathbf{B}^\top \mathbf{e}, \tag{7.29}$$

where $\alpha_d = (\alpha_{d,1}^\top \ \alpha_{d,2}^\top)^\top$, $\mathbf{e} = (\mathbf{e}_1^\top \ \mathbf{e}_2^\top)^\top$, $\nabla H_d(\alpha_d) = (\partial_{\alpha_{d,1}}^\top H_d(\alpha_d) \ \partial_{\alpha_{d,2}}^\top H_d(\alpha_d))^\top$ and

$$\mathbf{M} = \begin{bmatrix} \mathbf{M}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_2 \end{bmatrix}, \quad \mathbf{J}_{\mathcal{L}} = \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top - \mathbf{D}_{\mathcal{L}}^\top \\ \mathbf{D}_0 + \mathbf{D}_{\mathcal{L}} & \mathbf{0} \end{bmatrix}, \quad \mathbf{B} = \begin{bmatrix} \mathbf{B}_1 \\ \mathbf{0} \end{bmatrix}. \tag{7.30}$$

Plugging (7.28) into (7.27), a pH system in canonical form is obtained

$$\begin{aligned}\dot{\alpha}_d &= \mathbf{J} \nabla H_d(\alpha_d) + \mathbf{B} \mathbf{u}_\partial, & \text{where} \quad \mathbf{J} &= \mathbf{M}^{-1} \mathbf{J}_{\mathcal{L}} \mathbf{M}^{-1}, \\ \hat{\mathbf{y}}_\partial &= \mathbf{B}^\top \nabla H_d(\alpha_d), & \text{where} \quad \hat{\mathbf{y}}_\partial &= \mathbf{M}_\partial \mathbf{y}_\partial.\end{aligned}\tag{7.31}$$

The structure preserving character of the method is evident from the preservation at the discrete level of the power balance. The finite dimensional counterpart of the energy rate is given by

$$\begin{aligned}\dot{H}_d &= \nabla^\top H_d(\alpha_d) \dot{\alpha}_d, \\ &= \nabla^\top H_d(\alpha_d) \mathbf{J} \nabla H_d(\alpha_d) + \nabla^\top H_d(\alpha_d) \mathbf{B} \mathbf{u}_\partial, & \text{Skew-symmetry of } \mathbf{J} \\ &= \hat{\mathbf{y}}_\partial^\top \mathbf{u}_\partial.\end{aligned}\tag{7.32}$$

This result mimics its infinite dimensional equivalent (7.14).

Discretization of the weak form (7.22) Plugging the approximation into the weak form (7.22) a finite dimensional system with a different causality is obtained

$$\begin{aligned}
\begin{bmatrix} \mathbf{M}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_2 \end{bmatrix} \begin{pmatrix} \dot{\boldsymbol{\alpha}}_{d,1} \\ \dot{\boldsymbol{\alpha}}_{d,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top + \mathbf{D}_{-\mathcal{L}^*} \\ \mathbf{D}_0 - \mathbf{D}_{-\mathcal{L}^*}^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} + \begin{bmatrix} \mathbf{0} \\ \mathbf{B}_2 \end{bmatrix} \mathbf{u}_\partial, \\
\begin{bmatrix} \mathbf{M}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_2 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} &= \begin{pmatrix} \partial_{\boldsymbol{\alpha}_{d,1}} H_d(\boldsymbol{\alpha}_d) \\ \partial_{\boldsymbol{\alpha}_{d,2}} H_d(\boldsymbol{\alpha}_d) \end{pmatrix}, \\
\mathbf{M}_\partial \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{0} & \mathbf{B}_2^\top \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}.
\end{aligned} \tag{7.33}$$

1181 The differences with respect to formulation (7.24) reside in matrices $\mathbf{D}_{-\mathcal{L}^*}$, \mathbf{B}_2 , whose defi-
 1182 nitions are

$$D_{-\mathcal{L}^*}^{im} = \langle \phi_1^i, -\mathcal{L}^* \phi_2^m \rangle_{L^2(\Omega, \mathbb{A})}, \quad B_2^{mk} = \langle \mathcal{N}_{\partial,2} \phi_2^m, \phi_\partial^k \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \tag{7.34}$$

1183 where $i \in \{1, n_1\}$, $m \in \{1, n_2\}$, $k \in \{1, n_\partial\}$. System (7.33) can be put in canonical form by
 1184 replacing the co-energy variables by the discretized gradient.

1185 **Example: the irrotational shallow water equations** Consider as an example the
 1186 shallow water equations detailed in Sec. §3.2.3.3. The flow is assumed to be irrotational
 1187 ($\nabla \times \mathbf{v} = 0$). As a consequence the term \mathcal{G} in Eq. (3.36) vanishes. To fulfill Assumption 3,
 1188 the incoming volumetric flow is known at the boundary, so that a uniform Neumann condition
 1189 is imposed. This lead to the following boundary control system, defined on an open connected
 1190 set $\Omega \subset \mathbb{R}^2$

$$\begin{aligned}
\frac{\partial}{\partial t} \begin{pmatrix} \alpha_h \\ \boldsymbol{\alpha}_v \end{pmatrix} &= - \begin{bmatrix} 0 & \text{div} \\ \text{grad} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_h \\ \mathbf{e}_v \end{pmatrix}, & \alpha_h &\in L^2(\Omega), \\
& & \boldsymbol{\alpha}_v &\in L^2(\Omega, \mathbb{R}^2), \\
\begin{pmatrix} e_h \\ \mathbf{e}_v \end{pmatrix} &:= \begin{pmatrix} \delta_{\alpha_h} H \\ \delta_{\boldsymbol{\alpha}_v} H \end{pmatrix} = \begin{pmatrix} \frac{1}{2\rho} \|\boldsymbol{\alpha}_v\|^2 + \rho g \alpha_h \\ \frac{1}{\rho} \alpha_h \boldsymbol{\alpha}_v \end{pmatrix}, & e_h &\in H^1(\Omega), \\
& & \mathbf{e}_v &\in H^{\text{div}}(\Omega, \mathbb{R}^2), \\
u_\partial &= -\mathbf{e}_v \cdot \mathbf{n}, & u_\partial &\in \mathbb{R}, \\
y_\partial &= e_h, & y_\partial &\in \mathbb{R},
\end{aligned} \tag{7.35}$$

where the Hamiltonian is a non linear functional in the energy variables

$$H(\alpha_h, \boldsymbol{\alpha}_v) = \frac{1}{2} \int_\Omega \left\{ \frac{1}{\rho} \alpha_h \|\boldsymbol{\alpha}_v\|^2 + \rho g \alpha_h^2 \right\} d\Omega.$$

1191 The energy and co-energy variables are related to the physical variables (fluid height and
 1192 velocity) through Eqs. (3.33), (3.35). In this case $\mathbb{A} = \mathbb{R}$, $\mathbb{B} = \mathbb{R}^2$ and $\mathcal{L} = \text{grad}$, $-\mathcal{L}^* = \text{div}$.
 1193 This implies $H^\mathcal{L} = H^1(\Omega)$, $H^{-\mathcal{L}^*} = H^{\text{div}}(\Omega, \mathbb{R}^2)$. As shown in (3.37), the energy rate equals

$$\dot{H} = -\langle \mathbf{e}_v, \text{grad } e_h \rangle_{L^2(\Omega, \mathbb{R}^2)} - \langle \text{div } \mathbf{e}_v, e_h \rangle_{L^2(\Omega)} = \langle -\mathbf{e}_v \cdot \mathbf{n}, e_h \rangle_{L^2(\partial\Omega)}. \tag{7.36}$$

1194 The boundary operators are therefore given by

$$\begin{aligned}
u_\partial &= \mathcal{N}_{\partial,2} \mathbf{e}_v = -\gamma_n \mathbf{e}_v = -\mathbf{e}_v \cdot \mathbf{n}|_{\partial\Omega}, \\
y_\partial &= \mathcal{N}_{\partial,1} e_h = \gamma_0 e_h = e_h|_{\partial\Omega}.
\end{aligned} \tag{7.37}$$

1195 This system represents a particular example of the general formulation of the general frame-
 1196 work (7.11), together with boundary conditions (7.12). To obtain a finite dimensional system,
 1197 the test variables v_h , \mathbf{v}_v are introduced and the integration by parts is performed on the div
 1198 operator, leading to the weak form

$$\begin{aligned}
 \langle v_h, \partial_t \alpha_h \rangle_{L^2(\Omega)} &= \langle \text{grad } v_h, \mathbf{e}_v \rangle_{L^2(\Omega, \mathbb{R}^2)} + \langle \gamma_0 v_h, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega)}, \\
 \langle \mathbf{v}_v, \partial_t \alpha_v \rangle_{L^2(\Omega, \mathbb{R}^2)} &= - \langle \mathbf{v}_v, \text{grad } e_h \rangle_{L^2(\Omega, \mathbb{R}^2)}, \\
 \langle v_h, e_h \rangle_{L^2(\Omega)} &= \left\langle v_h, \frac{1}{2\rho} \|\alpha_v\|^2 + \rho g \alpha_h \right\rangle_{L^2(\Omega)}, \\
 \langle \mathbf{v}_v, \mathbf{e}_v \rangle_{L^2(\Omega, \mathbb{R}^2)} &= \left\langle \mathbf{v}_v, \frac{1}{\rho} \alpha_h \alpha_v \right\rangle_{L^2(\Omega, \mathbb{R}^2)}, \\
 \langle v_\partial, y_\partial \rangle_{L^2(\partial\Omega)} &= \langle v_\partial, \gamma_0 e_h \rangle_{L^2(\partial\Omega)}.
 \end{aligned} \tag{7.38}$$

1199 Introducing a Galerkin approximation as in (7.23)

$$\begin{aligned}
 v_h &\approx \sum_{i=1}^{n_h} \phi_h^i(\mathbf{x}) v_h^i, & \alpha_h &\approx \sum_{i=1}^{n_h} \phi_h^i(\mathbf{x}) \alpha_h^i(t), & e_h &\approx \sum_{i=1}^{n_h} \phi_h^i(\mathbf{x}) e_h^i(t), & \mathbf{x} \in \Omega, \\
 \mathbf{v}_v &\approx \sum_{i=1}^{n_v} \phi_v^i(\mathbf{x}) \mathbf{v}_v^i, & \alpha_v &\approx \sum_{i=1}^{n_v} \phi_v^i(\mathbf{x}) \alpha_v^i(t), & \mathbf{e}_v &\approx \sum_{i=1}^{n_v} \phi_v^i(\mathbf{x}) \mathbf{e}_v^i(t), & \mathbf{x} \in \Omega, \\
 v_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(s) v_\partial^i, & u_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(s) u_\partial^i(t), & y_\partial &\approx \sum_{i=1}^{n_\partial} \phi_\partial^i(s) y_\partial^i(t), & s \in \partial\Omega,
 \end{aligned} \tag{7.39}$$

1200 the finite dimensional system is obtained

$$\begin{aligned}
 \begin{bmatrix} \mathbf{M}_h & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_v \end{bmatrix} \begin{pmatrix} \dot{\alpha}_{d,h} \\ \dot{\alpha}_{d,v} \end{pmatrix} &= - \begin{bmatrix} \mathbf{0} & -\mathbf{D}_{\text{grad}}^\top \\ \mathbf{D}_{\text{grad}} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_h \\ \mathbf{e}_v \end{pmatrix} + \begin{bmatrix} \mathbf{B}_h \\ \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\
 \begin{bmatrix} \mathbf{M}_h & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_v \end{bmatrix} \begin{pmatrix} \mathbf{e}_h \\ \mathbf{e}_v \end{pmatrix} &= \begin{bmatrix} \partial_{\alpha_{d,h}} H_d(\alpha_{d,h}, \alpha_{d,v}) \\ \partial_{\alpha_{d,v}} H_d(\alpha_{d,h}, \alpha_{d,v}) \end{bmatrix}, \\
 \mathbf{M}_\partial \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{B}_h^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_h \\ \mathbf{e}_v \end{pmatrix}.
 \end{aligned} \tag{7.40}$$

1201 The matrices are defined as follows

$$\begin{aligned}
 M_h^{ij} &= \langle \phi_h^i, \phi_h^j \rangle_{L^2(\Omega)}, & D_{\text{grad}}^{mi} &= \langle \phi_v^m, \text{grad } \phi_h^i \rangle_{L^2(\Omega, \mathbb{R}^2)}, \\
 M_v^{mn} &= \langle \phi_v^m, \phi_v^n \rangle_{L^2(\Omega, \mathbb{R}^2)}, & B_h^{ik} &= \langle \gamma_0 \phi_h^i, \phi_\partial^k \rangle_{L^2(\partial\Omega)}, \\
 M_\partial^{lk} &= \langle \phi_\partial^l, \phi_\partial^k \rangle_{L^2(\partial\Omega)},
 \end{aligned} \tag{7.41}$$

where $i, j \in \{1, n_h\}$, $m, n \in \{1, n_v\}$, $l, k \in \{1, n_\partial\}$. The discretized gradient of the Hamiltonian read

$$\begin{aligned} \partial_{\alpha_{d,h}^i} H_d(\alpha_{d,h}, \alpha_{d,v}) &= \left\langle \phi_h^i, \frac{1}{2\rho} \left\| \sum_{r=1}^{n_2} \phi_v^r \alpha_v^r \right\|^2 + \rho g \sum_{r=1}^{n_1} \phi_h^r \alpha_h^r \right\rangle_{L^2(\Omega)}, \quad i \in \{1, n_h\}, \\ \partial_{\alpha_{d,v}^m} H_d(\alpha_{d,h}, \alpha_{d,v}) &= \left\langle \phi_v^m, \frac{1}{\rho} \left(\sum_{r=1}^{n_1} \phi_h^r \alpha_h^r \right) \left(\sum_{r=1}^{n_2} \phi_v^r \alpha_v^r \right) \right\rangle_{L^2(\Omega, \mathbb{R}^2)}, \quad m \in \{1, n_v\}. \end{aligned} \quad (7.42)$$

One possible finite element discretization for this problem can be found in [Pir89]. The non linear nature of the problem strongly complicates the analysis. The presence of shocks has to be accounted for in the numerical discretization. The proposed methodology has to cope with finite time shocks to become a valid alternative to already well established strategies.

7.1.2 Linear case

The general framework detailed in Sec. 7.1.1 is valid for both linear and non linear system. However, in the linear case a major simplification occurs since the constitutive law connecting energy and co-energy variables is easily invertible. This allows a description based on co-energy variables only.

To make the system linear, the additional assumption is introduced.

Assumption 4

The Hamiltonian is assumed to be a positive quadratic functional in the energy variables α_1, α_2 . Furthermore, the Hamiltonian is considered to be separable with respect to α_1, α_2 (this hypothesis is always met for the systems under consideration). Therefore, it can be expressed as

$$H = \frac{1}{2} \langle \alpha_1, \mathcal{Q}_1 \alpha_1 \rangle_{L^2(\Omega, \mathbb{A})} + \frac{1}{2} \langle \alpha_2, \mathcal{Q}_2 \alpha_2 \rangle_{L^2(\Omega, \mathbb{B})}, \quad (7.43)$$

where $\mathcal{Q}_1, \mathcal{Q}_2$ are positive symmetric operators, bounded from below and above

$$m_1 \mathbf{I}_{\mathbb{A}} \leq \mathcal{Q}_1 \leq M_1 \mathbf{I}_{\mathbb{A}}, \quad m_2 \mathbf{I}_{\mathbb{B}} \leq \mathcal{Q}_2 \leq M_2 \mathbf{I}_{\mathbb{B}}, \quad m_1 > 0, m_2 > 0, M_1 > 0, M_2 > 0,$$

where $\mathbf{I}_{\mathbb{A}}, \mathbf{I}_{\mathbb{B}}$ are the identity operator in \mathbb{A}, \mathbb{B} respectively. Because of Assumption 4, the co-energy variables are given by

$$e_1 := \delta_{\alpha_1} H = \mathcal{Q}_1 \alpha_1, \quad e_2 := \delta_{\alpha_2} H = \mathcal{Q}_2 \alpha_2 \quad (7.44)$$

Since $\mathcal{Q}_1, \mathcal{Q}_2$ are positive bounded from below and above, it is possible to invert them to obtain

$$\alpha_1 = \mathcal{Q}_1^{-1} e_1 = \mathcal{M}_1 e_1, \quad \alpha_2 = \mathcal{Q}_2^{-1} e_2 = \mathcal{M}_2 e_2, \quad \mathcal{M}_1 := \mathcal{Q}_1^{-1}, \mathcal{M}_2 := \mathcal{Q}_2^{-1}. \quad (7.45)$$

1224 The Hamiltonian is then written in terms of co-energy variables as

$$H = \frac{1}{2} \langle \mathbf{e}_1, \mathcal{M}_1 \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \frac{1}{2} \langle \mathbf{e}_2, \mathcal{M}_2 \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})}. \quad (7.46)$$

1225 Under assumptions 2, 3, 4, a pH linear system is expressed as

$$\begin{bmatrix} \mathcal{M}_1 & 0 \\ 0 & \mathcal{M}_2 \end{bmatrix} \partial_t \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} = \begin{bmatrix} 0 & -\mathbf{L}^\top - \mathcal{L}^* \\ \mathbf{L} + \mathcal{L} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{matrix} \mathbf{e}_1 \in H^\mathcal{L}, \\ \mathbf{e}_2 \in H^{-\mathcal{L}*}. \end{matrix} \quad (7.47)$$

1226 If Eq. (7.9) holds the boundary variables equal

$$\mathbf{u}_\partial = \mathcal{N}_2 \mathbf{e}_2, \quad \mathbf{y}_\partial = \mathcal{N}_1 \mathbf{e}_1, \quad \mathbf{u}_\partial, \mathbf{y}_\partial \in \mathbb{R}^m. \quad (7.48)$$

1227 Whereas if Eq. (7.10) holds, then

$$\mathbf{u}_\partial = \mathcal{N}_1 \mathbf{e}_1, \quad \mathbf{y}_\partial = \mathcal{N}_2 \mathbf{e}_2, \quad \mathbf{u}_\partial, \mathbf{y}_\partial \in \mathbb{R}^m. \quad (7.49)$$

1228 From equation (7.46), the power balance reads

$$\begin{aligned} \dot{H} &= \langle \mathbf{e}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathbf{e}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})}, \\ &= \langle \mathbf{e}_1, -\mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathbf{e}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \\ &= \langle \mathcal{N}_{\partial,1} \mathbf{e}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ &= \langle \mathbf{y}_\partial, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \quad (7.50)$$

1229 To get a finite dimensional approximation the same procedure detailed in Sec. §7.1.1 is
1230 followed. The only difference is that there is no need to discretize the constitutive relations
1231 as those are already incorporated in the dynamics.

1232 Once the system is put into weak form, if the operator $-\mathcal{L}^*$ is integrated by parts, one
1233 obtains the weak form

$$\begin{aligned} \langle \mathbf{v}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ \langle \mathbf{v}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}, \\ \langle \mathbf{v}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathbf{v}_\partial, \mathcal{N}_{\partial,1} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \quad (7.51)$$

1234 Otherwise, if operator \mathcal{L} is integrated by parts, it is computed

$$\begin{aligned} \langle \mathbf{v}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})}, \\ \langle \mathbf{v}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} + \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ \langle \mathbf{v}_\partial, \mathbf{y}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathbf{v}_\partial, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}. \end{aligned} \quad (7.52)$$

1235 After introducing a Galerkin approximation as in (7.23), the discretized version of the weak
1236 form (7.51) reads

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\mathcal{M}_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\mathcal{M}_2} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_1 \\ \dot{\mathbf{e}}_2 \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top - \mathbf{D}_{\mathcal{L}}^\top \\ \mathbf{D}_0 + \mathbf{D}_{\mathcal{L}} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} + \begin{bmatrix} \mathbf{B}_1 \\ \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{M}_\partial \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{B}_1^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}. \end{aligned} \quad (7.53)$$

1237 The only difference with respect to Eq. (7.24) concerns the mass matrices

$$M_{\mathcal{M}_1}^{ij} = \langle \phi_1^i, \mathcal{M}_1 \phi_1^j \rangle_{L^2(\Omega, \mathbb{A})}, \quad M_{\mathcal{M}_2}^{mn} = \langle \phi_2^m, \mathcal{M}_2 \phi_2^n \rangle_{L^2(\Omega, \mathbb{B})} \quad i, j \in \{1, n_1\}, \quad m, n \in \{1, n_2\}. \quad (7.54)$$

1238 If the Galerkin approximation is applied to the weak form (7.52), it is obtained

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\mathcal{M}_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\mathcal{M}_2} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_1 \\ \dot{\mathbf{e}}_2 \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top + \mathbf{D}_{-\mathcal{L}^*}^\top \\ \mathbf{D}_0 - \mathbf{D}_{-\mathcal{L}^*}^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} + \begin{bmatrix} \mathbf{0} \\ \mathbf{B}_2 \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{M}_\partial \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{0} & \mathbf{B}_2^\top \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}. \end{aligned} \quad (7.55)$$

1239 In both cases, it is easy to verify that the Hamiltonian

$$H_d = \frac{1}{2} \mathbf{e}_1^\top \mathbf{M}_{\mathcal{M}_1} \mathbf{e}_1 + \frac{1}{2} \mathbf{e}_2^\top \mathbf{M}_{\mathcal{M}_2} \mathbf{e}_2, \quad (7.56)$$

1240 once differentiated in time, provides the energy rate

$$\dot{H}_d = \mathbf{y}_\partial^\top \mathbf{M}_\partial \mathbf{u}_\partial = \hat{\mathbf{y}}_\partial^\top \mathbf{u}_\partial, \quad \text{where} \quad \hat{\mathbf{y}}_\partial := \mathbf{M}_\partial \mathbf{y}_\partial. \quad (7.57)$$

1241 This result mimics its finite dimensional counterpart (7.50).

1242 7.1.3 Linear flexible structures

1243 In this section, some linear example from the elasticity realms are considered. We restrict
1244 the discussion to linear problems. This case is anyway significant, as these examples are
1245 frequently encountered in engineering applications.

1246 7.1.3.1 Euler-Bernoulli beam

1247 We reconsider the example discussed in Sec. §3.2.3.2. The relation between energy and
1248 co-energy variables is given by Eqs. (3.24), (3.26)

$$\alpha_w = \rho A e_w, \quad \alpha_\kappa = \frac{1}{EI} e_\kappa \quad (7.58)$$

1249 The coefficients ρ, A, E and I are the mass density, the cross section area, Young's modulus
1250 of elasticity and the moment of inertia of the cross section.

1251 **Control through forces and torques** Given an interval $\Omega = (0, L)$, a thin beam under
 1252 free boundary condition (forces and torques imposed at the boundary) can be modeled in
 1253 terms of co-energy variables by the following system

$$\begin{bmatrix} \rho A & 0 \\ 0 & (EI)^{-1} \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{bmatrix} 0 & -\partial_{xx} \\ \partial_{xx} & 0 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \begin{matrix} e_w \in H^2(\Omega), \\ e_\kappa \in H^2(\Omega), \end{matrix} \quad (7.59a)$$

$$\mathbf{u}_\partial = \begin{bmatrix} 0 & \gamma_0 \\ 0 & -\gamma_1 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \mathbf{u}_\partial \in \mathbb{R}^4, \quad (7.59b)$$

$$\mathbf{y}_\partial = \begin{bmatrix} \gamma_1 & 0 \\ \gamma_0 & 0 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \mathbf{y}_\partial \in \mathbb{R}^4. \quad (7.59c)$$

1254 The boundary operator γ_0, γ_1 denote the trace and the first derivative trace along the bound-
 1255 ary. In a one-dimensional domain the boundary degenerates to two single points

$$\gamma_0 a = a|_{\partial\Omega} = \begin{pmatrix} -a(0) \\ +a(L) \end{pmatrix}, \quad \gamma_1 a = \partial_x a|_{\partial\Omega} = \begin{pmatrix} -\partial_x a(0) \\ +\partial_x a(L) \end{pmatrix}. \quad (7.60)$$

1256 In this case $\mathbb{A} = \mathbb{B} = \mathbb{R}$. The operators $\mathcal{M}_1, \mathcal{M}_2, \mathcal{L}, N_{\partial,1}, N_{\partial,2}$ read

$$\mathcal{M}_1 = \rho A, \quad \mathcal{M}_2 = (EI)^{-1}, \quad \mathcal{L} = \partial_{xx}, \quad N_{\partial,1} = \begin{bmatrix} \gamma_1 \\ \gamma_0 \end{bmatrix}, \quad N_{\partial,2} = \begin{bmatrix} \gamma_0 \\ -\gamma_1 \end{bmatrix}. \quad (7.61)$$

1257 The Hamiltonian is given by

$$H = \frac{1}{2} \int_{\Omega} \left\{ \rho A e_w^2 + (EI)^{-1} e_\kappa^2 \right\} d\Omega. \quad (7.62)$$

1258 Applying twice the integration by parts formula, one obtains the power balance

$$\begin{aligned} \dot{H} &= \langle e_w, \rho A \partial_t e_w \rangle_{L^2(\Omega)} + \langle e_\kappa, (EI)^{-1} \partial_t e_\kappa \rangle_{L^2(\Omega)}, \\ &= \langle e_w, -\partial_{xx} e_\kappa \rangle_{L^2(\Omega)} + \langle e_\kappa, \partial_{xx} e_w \rangle_{L^2(\Omega)}, \\ &= \langle \gamma_1 e_w, \gamma_0 e_\kappa \rangle_{\mathbb{R}^2} + \langle \gamma_0 e_w, -\gamma_1 e_\kappa \rangle_{\mathbb{R}^2}, \\ &= \langle \mathbf{y}_\partial, \mathbf{u}_\partial \rangle_{\mathbb{R}^4}. \end{aligned} \quad (7.63)$$

1259 Given the test functions v_w, v_κ , the weak form is readily obtained as

$$\begin{aligned} \langle v_w, \rho A \partial_t e_w \rangle_{L^2(\Omega)} &= \langle v_w, -\partial_{xx} e_\kappa \rangle_{L^2(\Omega)}, \\ \langle v_\kappa, (EI)^{-1} \partial_t e_\kappa \rangle_{L^2(\Omega)} &= \langle v_\kappa, \partial_{xx} e_w \rangle_{L^2(\Omega)}. \end{aligned} \quad (7.64)$$

1260 If the integration by parts is applied twice to the first line of Eq. (7.59a), it is obtained

$$\begin{aligned} \langle v_w, \rho A \partial_t e_w \rangle_{L^2(\Omega)} &= -\langle \partial_{xx} v_w, e_\kappa \rangle_{L^2(\Omega)} + \langle \gamma_1 v_w, (u_{\partial,1}, u_{\partial,2}) \rangle_{\mathbb{R}^2} + \langle \gamma_0 v_w, (u_{\partial,3}, u_{\partial,4}) \rangle_{\mathbb{R}^2}, \\ \langle v_\kappa, (EI)^{-1} \partial_t e_\kappa \rangle_{L^2(\Omega)} &= \langle v_\kappa, \partial_{xx} e_w \rangle_{L^2(\Omega)}. \end{aligned} \quad (7.65)$$

1261 Introducing a Galerkin discretization for test and efforts functions

$$v_w = \sum_{i=1}^{n_w} \phi_w^i v_w^i, \quad e_w = \sum_{i=1}^{n_w} \phi_w^i e_w^i(t), \quad v_\kappa = \sum_{i=1}^{n_\kappa} \phi_\kappa^i v_\kappa^i, \quad e_\kappa = \sum_{i=1}^{n_\kappa} \phi_\kappa^i e_\kappa^i(t), \quad (7.66)$$

1262 and considering that $\mathbf{u}_\partial \in \mathbb{R}^4$, $\mathbf{y}_\partial \in \mathbb{R}^4$, the following is obtained

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\rho A} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{EI^{-1}} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_w \\ \dot{\mathbf{e}}_\kappa \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_{\partial_{xx}}^\top \\ \mathbf{D}_{\partial_{xx}} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\kappa \end{pmatrix} + \begin{bmatrix} \mathbf{B}_w \\ \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{B}_w^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\kappa \end{pmatrix}. \end{aligned} \quad (7.67)$$

1263 The matrices $\mathbf{M}_{\rho A}$, $\mathbf{M}_{EI^{-1}}$, $\mathbf{D}_{\partial_{xx}}$ are defined as ($i, j \in \{1, n_w\}$, $m, n \in \{1, n_\kappa\}$)

$$M_{\rho A}^{ij} = \langle \phi_w^i, \rho A \phi_w^j \rangle_{L^2(\Omega)}, \quad M_{EI^{-1}}^{mn} = \langle \phi_\kappa^m, (EI)^{-1} \phi_\kappa^n \rangle_{L^2(\Omega)}, \quad D_{\partial_{xx}}^{mi} = \langle \phi_\kappa^m, \partial_{xx} \phi_w^i \rangle_{L^2(\Omega)}. \quad (7.68)$$

1264 The \mathbf{B}_w is composed of four column vectors $\mathbf{B}_w = [\mathbf{b}_w^1 \ \mathbf{b}_w^2 \ \mathbf{b}_w^3 \ \mathbf{b}_w^4]$

$$b_w^{1,i} = -\partial_x \phi_w^i(0), \quad b_w^{2,i} = \partial_x \phi_w^i(L), \quad b_w^{3,i} = -\phi_w^i(0), \quad b_w^{4,i} = \phi_w^i(L), \quad i \in \{1, n_w\}. \quad (7.69)$$

Control through linear and angular velocities Equivalently, the second line of Eq. (7.59a) could have been integrated by parts to control through the linear and angular velocities at the extremities. Consider the system with known forces and torques at the extremities

$$\begin{bmatrix} \rho A & 0 \\ 0 & (EI)^{-1} \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix} = \begin{bmatrix} 0 & -\partial_{xx} \\ \partial_{xx} & 0 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \begin{aligned} e_w &\in H^2(\Omega), \\ e_\kappa &\in H^2(\Omega), \end{aligned} \quad (7.70a)$$

$$\mathbf{u}_\partial = \begin{bmatrix} \gamma_1 & 0 \\ \gamma_0 & 0 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \mathbf{u}_\partial \in \mathbb{R}^4, \quad (7.70b)$$

$$\mathbf{y}_\partial = \begin{bmatrix} 0 & \gamma_0 \\ 0 & -\gamma_1 \end{bmatrix} \begin{pmatrix} e_w \\ e_\kappa \end{pmatrix}, \quad \mathbf{y}_\partial \in \mathbb{R}^4. \quad (7.70c)$$

1265 Once the system is put into weak form and the second line of Eq. (7.70a) is integrated twice,
1266 it is computed

$$\begin{aligned} \langle v_w, \rho A \partial_t e_w \rangle_{L^2(\Omega)} &= \langle v_w, -\partial_{xx} e_\kappa \rangle_{L^2(\Omega)}, \\ \langle v_\kappa, (EI)^{-1} \partial_t e_\kappa \rangle_{L^2(\Omega)} &= \langle \partial_{xx} v_\kappa, e_w \rangle_{L^2(\Omega)} + \langle \gamma_0 v_\kappa, (u_{\partial,1}, u_{\partial,2}) \rangle_{\mathbb{R}^2} + \langle -\gamma_1 v_\kappa, (u_{\partial,3}, u_{\partial,4}) \rangle_{\mathbb{R}^2}. \end{aligned} \quad (7.71)$$

1267 Replacing a Galerkin approximation, it is obtained

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\rho A} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{EI^{-1}} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_w \\ \dot{\mathbf{e}}_\kappa \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{D}_{-\partial_{xx}} \\ -\mathbf{D}_{-\partial_{xx}}^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\kappa \end{pmatrix} + \begin{bmatrix} \mathbf{0} \\ \mathbf{B}_\kappa \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{0} & \mathbf{B}_\kappa^\top \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\kappa \end{pmatrix}. \end{aligned} \quad (7.72)$$

1268 The matrix $\mathbf{D}_{-\partial_{xx}}$ is defined as

$$D_{-\partial_{xx}}^{im} = \left\langle \phi_w^i, -\partial_{xx}\phi_\kappa^m \right\rangle_{L^2(\Omega)}, \quad i, \in \{1, n_w\}, \quad m \in \{1, n_\kappa\}. \quad (7.73)$$

1269 The \mathbf{B}_κ is composed of four column vectors $\mathbf{B}_\kappa = [\mathbf{b}_\kappa^1 \mathbf{b}_\kappa^2 \mathbf{b}_\kappa^3 \mathbf{b}_\kappa^4]$

$$b_\kappa^{1,m} = -\phi_\kappa^m(0), \quad b_\kappa^{2,m} = \phi_\kappa^m(L), \quad b_\kappa^{3,m} = \partial_x \phi_\kappa^m(0), \quad b_\kappa^{4,m} = -\partial_x \phi_\kappa^m(L), \quad m \in \{1, n_\kappa\}. \quad (7.74)$$

1270 Both discretization require the use of Hermite polynomials to meet the regularity require-
1271 ment. Indeed, to lower the regularity requirement for the finite elements employed in the
1272 discretization, both lines can be integrated by parts. This will be discussed in Chap. 8.

1273 7.1.3.2 Kirchhoff plate

1274 The link between the energy and co-energy variables for the isotropic Kirchhoff model is the
1275 following (5.33)

$$\alpha_w = \rho h e_w, \quad \mathbf{A}_\kappa = \mathbf{C}_b \mathbf{E}_\kappa, \quad \text{where} \quad \mathbf{C}_b := \mathbf{D}_b^{-1} \quad (7.75)$$

1276 where ρ is the mass density, h the plate thickness and \mathbf{D}_b , the bending rigidity tensor, cf. Eq.
1277 (5.11). The bending compliance is given by

$$\mathbf{C}_b = \frac{12}{Eh^3} [(1 + \nu)(\cdot) - \nu \text{Tr}(\cdot) \mathbf{I}_{2 \times 2}]. \quad (7.76)$$

Given an open connected set $\Omega \subset \mathbb{R}^2$, the Kirchhoff plate model (5.42) in co-energy form controlled by forces and momenta is then expressed as

$$\begin{bmatrix} \rho h & 0 \\ 0 & \mathbf{C}_b \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix} = \begin{bmatrix} 0 & -\text{div Div} \\ \text{Hess} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}, \quad \begin{aligned} e_w &\in H^2(\Omega), \\ \mathbf{E}_\kappa &\in H^{\text{div Div}}(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2}), \end{aligned} \quad (7.77a)$$

$$\mathbf{u}_\partial = \begin{bmatrix} 0 & \gamma_{nn,1} \\ 0 & \gamma_{nn} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}, \quad \mathbf{u}_\partial \in \mathbb{R}^2, \quad (7.77b)$$

$$\mathbf{y}_\partial = \begin{bmatrix} \gamma_0 & 0 \\ \gamma_1 & 0 \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{E}_\kappa \end{pmatrix}, \quad \mathbf{y}_\partial \in \mathbb{R}^2, \quad (7.77c)$$

1278 We recall the expressions of the trace maps

$$\begin{aligned}\gamma_0 a &= a|_{\partial\Omega}, & \gamma_{nn,1} \mathbf{A} &= -\mathbf{n} \cdot \text{Div } \mathbf{A} - \partial_s(\mathbf{A} : (\mathbf{n} \otimes \mathbf{s}))|_{\partial\Omega}, \\ \gamma_1 a &= \partial_{\mathbf{n}} a|_{\partial\Omega}, & \gamma_{nn} \mathbf{A} &= \mathbf{A} : (\mathbf{n} \otimes \mathbf{n})|_{\partial\Omega}.\end{aligned}\quad (7.78)$$

1279 In this case, the sets are $\mathbb{A} = \mathbb{R}$, $\mathbb{B} = \mathbb{R}_{\text{sym}}^{2 \times 2}$. The operators $\mathcal{M}_1, \mathcal{M}_2, \mathcal{L}, N_{\partial,1}, N_{\partial,2}$ are

$$\mathcal{M}_1 = \rho h, \quad \mathcal{M}_2 = \mathbf{C}_b, \quad \mathcal{L} = \text{Hess}, \quad N_{\partial,1} = \begin{bmatrix} \gamma_0 \\ \gamma_1 \end{bmatrix}, \quad N_{\partial,2} = \begin{bmatrix} \gamma_{nn,1} \\ \gamma_{nn} \end{bmatrix}. \quad (7.79)$$

1280 The energy rate from Eq. (5.39) equals $\dot{H} = \langle \mathbf{y}_{\partial}, \mathbf{u}_{\partial} \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}$. Introducing the test
1281 functions $(v_w, \mathbf{V}_{\kappa})$ and integrating by parts twice the first line of (7.77a) one gets

$$\begin{aligned}\langle v_w, \rho h \partial_t e_w \rangle_{L^2(\Omega)} &= -\langle \text{Hess } v_w, \mathbf{E}_{\kappa} \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})} + \langle \gamma_0 v_w, u_{\partial,1} \rangle_{L^2(\partial\Omega)} + \langle \gamma_1 v_w, u_{\partial,2} \rangle_{L^2(\partial\Omega)}, \\ \langle \mathbf{V}_{\kappa}, \mathbf{C}_b \partial_t \mathbf{V}_{\kappa} \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})} &= \langle \mathbf{V}_{\kappa}, \text{Hess } e_w \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})}.\end{aligned}\quad (7.80)$$

1282 Introducing a Galerkin discretization for test and efforts functions

$$\begin{aligned}v_w &= \sum_{i=1}^{n_w} \phi_w^i v_w^i, & \mathbf{V}_{\kappa} &= \sum_{i=1}^{n_{\kappa}} \Phi_{\kappa}^i v_{\kappa}^i, & v_{\partial} &= \sum_{i=1}^{n_{\partial}} \phi_{\partial}^i v_{\partial}^i, & \mathbf{y}_{\partial} &= \sum_{i=1}^{n_{\partial}} \phi_{\partial}^i y_{\partial}^i. \\ e_w &= \sum_{i=1}^{n_w} \phi_w^i e_w^i, & \mathbf{E}_{\kappa} &= \sum_{i=1}^{n_{\kappa}} \Phi_{\kappa}^i e_{\kappa}^i, & \mathbf{u}_{\partial} &= \sum_{i=1}^{n_{\partial}} \phi_{\partial}^i u_{\partial}^i,\end{aligned}\quad (7.81)$$

1283 the following finite dimensional system is obtained

$$\begin{aligned}\begin{bmatrix} \mathbf{M}_{\rho h} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\mathbf{C}_b} \end{bmatrix} \begin{pmatrix} \dot{e}_w \\ \dot{e}_{\kappa} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_{\text{Hess}}^{\top} \\ \mathbf{D}_{\text{Hess}} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_{\kappa} \end{pmatrix} + \begin{bmatrix} \mathbf{B}_w & \mathbf{B}_{\partial_n w} \\ \mathbf{0} & \mathbf{0} \end{bmatrix} \mathbf{u}_{\partial}, \\ \mathbf{M}_{\partial} \mathbf{y}_{\partial} &= \begin{bmatrix} \mathbf{B}_w^{\top} & \mathbf{0} \\ \mathbf{B}_{\partial_n w}^{\top} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_{\kappa} \end{pmatrix}.\end{aligned}\quad (7.82)$$

1284 The matrices $\mathbf{M}_{\rho h}, \mathbf{M}_{\mathbf{C}_b}, \mathbf{D}_{\text{Hess}}$ are defined as $(i, j \in \{1, n_w\}, m, n \in \{1, n_{\kappa}\})$

$$M_{\rho h}^{ij} = \langle \phi_w^i, \rho h \phi_w^j \rangle_{L^2(\Omega)}, \quad M_{\mathbf{C}_b}^{mn} = \langle \Phi_{\kappa}^m, \mathbf{C}_b \Phi_{\kappa}^n \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})}, \quad D_{\text{Hess}}^{mi} = \langle \Phi_{\kappa}^m, \text{Hess } \phi_w^i \rangle_{L^2(\Omega)}. \quad (7.83)$$

1285 Matrices $\mathbf{B}_w, \mathbf{B}_{\partial_n w}$ are given by

$$B_w^{il} = \langle \gamma_0 \phi_w^i, \phi_{\partial,1}^l \rangle_{L^2(\partial\Omega)}, \quad B_{\partial_n w}^{il} = \langle \gamma_1 \phi_w^i, \phi_{\partial,2}^l \rangle_{L^2(\partial\Omega)}, \quad l \in \{1, n_{\partial}\}. \quad (7.84)$$

1286 This kind of discretization requires H^2 conforming element. The construction of those is
1287 rather involved [AFS68, Bel69] and they are computationally expensive. Nevertheless, this
1288 kind of discretization is able to handle generic boundary conditions [GSV18]. For this reason,
1289 it is the most adapted for the pH framework.

To lower the regularity requirement for the finite elements many non conforming discretization have been proposed. The most employed is the Hellan-Herrmann-Johnson element [AB85, BR90]. However, this method does not handle generic non homogeneous boundary conditions. Given the unavailability of the boundary for interconnections, the modularity feature of pHs cannot be fully exploited.

Remark 9 (On the $H^{\text{div Div}}$ space)

Equivalently, the second line of Eq. (7.77a) can be integrated by parts twice to obtain a discretized system whose input are the linear velocity and the angular velocity at the boundary. However, while for the H^2 space conforming finite elements are available, for the $H^{\text{div Div}}$ no conforming finite elements have been proposed. This makes the discretization unfeasible.

7.1.3.3 Mindlin plate

Using Eqs. (5.22) and (5.24), the relation between co-energy and energy variables for the isotropic Mindlin plate is found to be

$$\begin{aligned} \alpha_w &= \rho h e_w, & \alpha_\theta &= I_\theta e_\theta, & I_\theta &:= \rho h^3 / 12, \\ \mathbf{A}_\kappa &= \mathbf{C}_b \mathbf{E}_\kappa, & \alpha_\gamma &= C_s e_\gamma, & C_s &:= 1 / (K_{\text{sh}} G h), \end{aligned} \tag{7.85}$$

where K_{sh} is the shear correction factor, G the shear modulus. The other variables have the same meaning as in Sec. §7.1.3.2.

Control through forces and torques A pH representation in co-energy variables with known forces and momenta at the boundary is given by the system

$$\begin{bmatrix} \rho h & 0 & 0 & 0 \\ \mathbf{0} & I_\theta & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{C}_b & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & C_s \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} e \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix} = \begin{bmatrix} 0 & 0 & 0 & \text{div} \\ \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{I}_{2 \times 2} \\ \mathbf{0} & \text{Grad} & \mathbf{0} & \mathbf{0} \\ \text{grad} & -\mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad \begin{aligned} e_w &\in H^1(\Omega), \\ \mathbf{e}_\theta &\in H^{\text{Grad}}(\Omega, \mathbb{R}^2), \\ \mathbf{E}_\kappa &\in H^{\text{Div}}(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2}), \\ \mathbf{e}_\gamma &\in H^{\text{div}}(\Omega, \mathbb{R}^2), \end{aligned} \quad (7.86a)$$

$$\mathbf{u}_\partial = \begin{bmatrix} 0 & 0 & 0 & \gamma_n \\ 0 & 0 & \gamma_{nn} & 0 \\ 0 & 0 & \gamma_{ns} & 0 \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad \mathbf{u}_\partial \in \mathbb{R}^3, \quad (7.86b)$$

$$\mathbf{y}_\partial = \begin{bmatrix} \gamma_0 & 0 & 0 & 0 \\ 0 & \gamma_n & 0 & 0 \\ 0 & \gamma_s & 0 & 0 \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad \mathbf{y}_\partial \in \mathbb{R}^3. \quad (7.86c)$$

1309 The trace operators are defined as

$$\begin{aligned} \gamma_0 a &= a|_{\partial\Omega}, & \gamma_n \mathbf{a} &= \mathbf{a} \cdot \mathbf{n}|_{\partial\Omega}, & \gamma_{nn} \mathbf{A} &= \mathbf{A} : (\mathbf{n} \otimes \mathbf{n})|_{\partial\Omega}, \\ \gamma_s \mathbf{a} &= \mathbf{a} \cdot \mathbf{s}|_{\partial\Omega}, & \gamma_{ns} \mathbf{A} &= \mathbf{A} : (\mathbf{n} \otimes \mathbf{s})|_{\partial\Omega}. \end{aligned} \quad (7.87)$$

1310 The variables assume value in the sets $\mathbb{A} = \mathbb{R} \times \mathbb{R}^2$, $\mathbb{B} = \mathbb{R}_{\text{sym}}^{2 \times 2} \times \mathbb{R}^2$. The mass operators
1311 are given by

$$\mathcal{M}_1 = \begin{bmatrix} \rho h & 0 \\ \mathbf{0} & I_\theta \end{bmatrix}, \quad \mathcal{M}_2 = \begin{bmatrix} \mathbf{C}_b & \mathbf{0} \\ \mathbf{0} & C_s \end{bmatrix}. \quad (7.88)$$

1312 The \mathbf{L} , \mathcal{L} , $\mathcal{N}_{\partial,1}$, $\mathcal{N}_{\partial,2}$ operators are

$$\mathbf{L} = \begin{bmatrix} \mathbf{0} & \mathbf{0} \\ \mathbf{0} & -\mathbf{I}_{2 \times 2} \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} \mathbf{0} & \text{Grad} \\ \text{grad} & \mathbf{0} \end{bmatrix}, \quad \mathcal{N}_{\partial,1} = \begin{bmatrix} \gamma_0 & 0 \\ 0 & \gamma_n \\ 0 & \gamma_s \end{bmatrix}, \quad \mathcal{N}_{\partial,2} = \begin{bmatrix} 0 & \gamma_n \\ \gamma_{nn} & 0 \\ \gamma_{ns} & 0 \end{bmatrix}. \quad (7.89)$$

1313 The energy rate is retrieved from Eq. (5.26) $\dot{H} = \langle \mathbf{y}_\partial, \mathbf{u}_\partial \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}$. Introducing the test
1314 functions $(v_w, \mathbf{v}_\theta, \mathbf{V}_\kappa, \mathbf{v}_\gamma)$ and integrating by parts the first two lines of (7.86a) one gets

$$\begin{aligned} \langle v_w, \rho h \partial_t e_w \rangle_{L^2(\Omega)} &= -\langle \text{grad } v_w, \mathbf{e}_\gamma \rangle_{L^2(\Omega, \mathbb{R}^2)} + \langle \gamma_0 v_w, u_{\partial,1} \rangle_{L^2(\partial\Omega)}, \\ \langle \mathbf{v}_\theta, I_\theta \partial_t \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}^2)} &= -\langle \text{Grad } \mathbf{v}_\theta, \mathbf{E}_\kappa \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})} + \langle \mathbf{v}_\theta, \mathbf{e}_\gamma \rangle_{L^2(\Omega)} + \langle \gamma_0 \mathbf{v}_\theta, \gamma_n \mathbf{E}_\kappa \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}, \\ \langle \mathbf{V}_\kappa, \mathbf{C}_b \partial_t \mathbf{E}_\kappa \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})} &= \langle \mathbf{V}_\kappa, \text{Grad } \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})}, \\ \langle \mathbf{v}_\gamma, C_s \partial_t \mathbf{e}_\gamma \rangle_{L^2(\Omega, \mathbb{R}^2)} &= \langle \mathbf{v}_\gamma, \text{grad } e_w \rangle_{L^2(\Omega, \mathbb{R}^2)} - \langle \mathbf{v}_\gamma, \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}^2)}. \end{aligned} \quad (7.90)$$

1315 The term $\langle \gamma_0 \mathbf{v}_\theta, \mathbf{u}_{\partial,2} \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}$ can be decomposed in its tangential and normal components

$$\langle \gamma_0 \mathbf{v}_\theta, \gamma_n \mathbf{E}_\kappa \rangle_{L^2(\partial\Omega, \mathbb{R}^2)} = \langle \gamma_n \mathbf{v}_\theta, u_{\partial,2} \rangle_{L^2(\partial\Omega)} + \langle \gamma_s \mathbf{v}_\theta, u_{\partial,3} \rangle_{L^2(\partial\Omega)} \quad (7.91)$$

1316 Introducing a Galerkin discretization for test and efforts functions

$$\begin{aligned} v_w &= \sum_{i=1}^{n_w} \phi_w^i v_w^i, & \mathbf{v}_\theta &= \sum_{i=1}^{n_\theta} \phi_\theta^i v_\theta^i, & \mathbf{V}_\kappa &= \sum_{i=1}^{n_\kappa} \Phi_\kappa^i v_\kappa^i, & \mathbf{v}_\gamma &= \sum_{i=1}^{n_\gamma} \phi_\gamma^i v_\gamma^i, & \mathbf{v}_\partial &= \sum_{i=1}^{n_\partial} \phi_\partial^i v_\partial^i, \\ e_w &= \sum_{i=1}^{n_w} \phi_w^i e_w^i, & \mathbf{e}_\theta &= \sum_{i=1}^{n_\theta} \phi_\theta^i e_\theta^i, & \mathbf{E}_\kappa &= \sum_{i=1}^{n_\kappa} \Phi_\kappa^i e_\kappa^i, & \mathbf{e}_\gamma &= \sum_{i=1}^{n_\gamma} \phi_\gamma^i e_\gamma^i, & \mathbf{u}_\partial &= \sum_{i=1}^{n_\partial} \phi_\partial^i u_\partial^i, \\ & & & & & & & & \mathbf{y}_\partial &= \sum_{i=1}^{n_\partial} \phi_\partial^i y_\partial^i. \end{aligned} \quad (7.92)$$

1317 the following finite dimensional system is obtained

$$\begin{aligned} \text{Diag} \begin{bmatrix} \mathbf{M}_{\rho h} \\ \mathbf{M}_{I_\theta} \\ \mathbf{M}_{\mathbf{C}_b} \\ \mathbf{M}_{\mathbf{C}_s} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_w \\ \dot{\mathbf{e}}_\theta \\ \dot{\mathbf{e}}_\kappa \\ \dot{\mathbf{e}}_\gamma \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{0} & -\mathbf{D}_{\text{grad}}^\top \\ \mathbf{0} & \mathbf{0} & -\mathbf{D}_{\text{Grad}}^\top & -\mathbf{D}_0^\top \\ \mathbf{0} & \mathbf{D}_{\text{Grad}} & \mathbf{0} & \mathbf{0} \\ \mathbf{D}_{\text{grad}} & \mathbf{D}_0 & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\theta \\ \mathbf{e}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix} + \begin{bmatrix} \mathbf{B}_w & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{\theta_n} & \mathbf{B}_{\theta_s} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{M}_\partial \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{B}_w^\top & \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{\theta_n}^\top & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{\theta_s}^\top & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_w \\ \mathbf{e}_\theta \\ \mathbf{e}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}. \end{aligned} \quad (7.93)$$

1318 The notation Diag denotes a block diagonal matrix. The mass matrices $\mathbf{M}_{\rho h}$, \mathbf{M}_{I_θ} , $\mathbf{M}_{\mathbf{C}_b}$, $\mathbf{M}_{\mathbf{C}_s}$
1319 are computed as

$$\begin{aligned} M_{\rho h}^{ij} &= \langle \phi_w^i, \rho h \phi_w^j \rangle_{L^2(\Omega)}, & M_{\mathbf{C}_b}^{pq} &= \langle \Phi_\kappa^p, \mathbf{C}_b \Phi_\kappa^q \rangle_{L^2(\Omega, \mathbb{R}^{2 \times 2})}, \\ M_{I_\theta}^{mn} &= \langle \phi_\kappa^m, I_\theta \phi_\kappa^n \rangle_{L^2(\Omega, \mathbb{R}^2)}, & M_{\mathbf{C}_s}^{rs} &= \langle \phi_\gamma^r, \mathbf{C}_s \phi_\gamma^s \rangle_{L^2(\Omega, \mathbb{R}^2)}, \end{aligned} \quad (7.94)$$

1320 where $i, j \in \{1, n_w\}$, $m, n \in \{1, n_\theta\}$, $p, q \in \{1, n_\kappa\}$, $r, s \in \{1, n_\gamma\}$. Matrices \mathbf{D}_{grad} , \mathbf{D}_{Grad} , \mathbf{D}_0
1321 assume the form

$$\begin{aligned} D_{\text{grad}}^{rj} &= \langle \phi_\gamma^r, \text{grad} \phi_w^j \rangle_{L^2(\Omega, \mathbb{R}^2)}, & D_0^{rn} &= -\langle \phi_\gamma^r, \phi_\theta^n \rangle_{L^2(\Omega, \mathbb{R}^2)}, \\ D_{\text{Grad}}^{pn} &= \langle \Phi_\kappa^p, \text{Grad} \phi_\theta^n \rangle_{L^2(\Omega, \mathbb{R}^{2 \times 2})}, \end{aligned} \quad (7.95)$$

1322 Matrices \mathbf{B}_w , \mathbf{B}_{θ_n} , \mathbf{B}_{θ_s} are computed as ($l \in \{1, n_\partial\}$)

$$B_w^{il} = \langle \gamma_0 \phi_w^i, \phi_{\partial,1}^l \rangle_{L^2(\partial\Omega)}, \quad B_{\theta_n}^{ml} = \langle \gamma_n \phi_\theta^m, \phi_{\partial,2}^l \rangle_{L^2(\partial\Omega)}, \quad B_{\theta_s}^{ml} = \langle \gamma_s \phi_\theta^m, \phi_{\partial,3}^l \rangle_{L^2(\partial\Omega)}. \quad (7.96)$$

Control through linear and angular velocities If instead the opposite causality is considered, the continuous system read

$$\begin{bmatrix} \rho h & 0 & 0 & 0 \\ \mathbf{0} & I_\theta & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{C}_b & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} & C_s \end{bmatrix} \frac{\partial}{\partial t} \begin{pmatrix} e \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix} = \begin{bmatrix} 0 & 0 & 0 & \text{div} \\ \mathbf{0} & \mathbf{0} & \text{Div} & \mathbf{I}_{2 \times 2} \\ \mathbf{0} & \text{Grad} & \mathbf{0} & \mathbf{0} \\ \text{grad} & -\mathbf{I}_{2 \times 2} & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad (7.97a)$$

$$\mathbf{u}_\partial = \begin{bmatrix} \gamma_0 & 0 & 0 & 0 \\ 0 & \gamma_n & 0 & 0 \\ 0 & \gamma_s & 0 & 0 \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad \mathbf{u}_\partial \in \mathbb{R}^3, \quad (7.97b)$$

$$\mathbf{y}_\partial = \begin{bmatrix} 0 & 0 & 0 & \gamma_n \\ 0 & 0 & \gamma_{nn} & 0 \\ 0 & 0 & \gamma_{ns} & 0 \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{E}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}, \quad \mathbf{y}_\partial \in \mathbb{R}^3. \quad (7.97c)$$

1323 Integrating by parts the last two lines of (7.97a) one gets

$$\begin{aligned} \langle v_w, \rho h \partial_t e_w \rangle_{L^2(\Omega)} &= \langle v_w, \text{div } \mathbf{e}_\gamma \rangle_{L^2(\Omega, \mathbb{R}^2)}, \\ \langle \mathbf{v}_\theta, I_\theta \partial_t \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}^2)} &= \langle \mathbf{v}_\theta, \text{Div } \mathbf{E}_\kappa \rangle_{L^2(\Omega, \mathbb{R}^2)} + \langle \mathbf{v}_\theta, \mathbf{e}_\gamma \rangle_{L^2(\Omega)}, \\ \langle \mathbf{V}_\kappa, \mathbf{C}_b \partial_t \mathbf{E}_\kappa \rangle_{L^2(\Omega, \mathbb{R}_{\text{sym}}^{2 \times 2})} &= - \langle \text{Div } \mathbf{V}_\kappa, \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}^2)} + \langle \gamma_n \mathbf{V}_\kappa, \gamma_0 \mathbf{e}_\theta \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}, \\ \langle \mathbf{v}_\gamma, C_s \partial_t \mathbf{e}_\gamma \rangle_{L^2(\Omega, \mathbb{R}^2)} &= - \langle \text{div } \mathbf{v}_\gamma, e_w \rangle_{L^2(\Omega)} - \langle \mathbf{v}_\gamma, \mathbf{e}_\theta \rangle_{L^2(\Omega, \mathbb{R}^2)} + \langle \gamma_0 v_w, u_{\partial,1} \rangle_{L^2(\partial\Omega)}. \end{aligned} \quad (7.98)$$

1324 The term $\langle \gamma_n \mathbf{V}_\kappa, \gamma_0 \mathbf{e}_\theta \rangle_{L^2(\partial\Omega, \mathbb{R}^2)}$ can be decomposed in its tangential and normal components

$$\langle \gamma_n \mathbf{V}_\kappa, \gamma_0 \mathbf{e}_\theta \rangle_{L^2(\partial\Omega, \mathbb{R}^2)} = \langle \gamma_{nn} \mathbf{V}_\kappa, u_{\partial,2} \rangle_{L^2(\partial\Omega)} + \langle \gamma_{ns} \mathbf{V}_\kappa, u_{\partial,3} \rangle_{L^2(\partial\Omega)}. \quad (7.99)$$

1325 Plugging approximation (7.92) into this system, one computes

$$\begin{aligned} \text{Diag} \begin{bmatrix} \mathbf{M}_{\rho h} \\ \mathbf{M}_{I_\theta} \\ \mathbf{M}_{\mathbf{C}_b} \\ \mathbf{M}_{C_s} \end{bmatrix} \begin{pmatrix} \dot{e}_w \\ \dot{\mathbf{e}}_\theta \\ \dot{\mathbf{E}}_\kappa \\ \dot{\mathbf{e}}_\gamma \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{D}_{\text{div}} \\ \mathbf{0} & \mathbf{0} & \mathbf{D}_{\text{Div}} & -\mathbf{D}_0^\top \\ \mathbf{0} & -\mathbf{D}_{\text{Div}}^\top & \mathbf{0} & \mathbf{0} \\ -\mathbf{D}_{\text{div}}^\top & \mathbf{D}_0 & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{e}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix} + \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{M_{nn}} & \mathbf{B}_{M_{ns}} \\ \mathbf{B}_{q_n} & \mathbf{0} & \mathbf{0} \end{bmatrix} \mathbf{u}_\partial, \\ \mathbf{M}_{\partial} \mathbf{y}_\partial &= \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{0} & \mathbf{B}_{q_n}^\top \\ \mathbf{0} & \mathbf{0} & \mathbf{B}_{M_{nn}}^\top & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{B}_{M_{ns}}^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} e_w \\ \mathbf{e}_\theta \\ \mathbf{e}_\kappa \\ \mathbf{e}_\gamma \end{pmatrix}. \end{aligned} \quad (7.100)$$

1326 Matrices \mathbf{D}_{div} , \mathbf{D}_{Div} assume the form ($i, j \in \{1, n_w\}$, $m, n \in \{1, n_\theta\}$, $p, q \in \{1, n_\kappa\}$, $r, s \in$
1327 $\{1, n_\gamma\}$)

$$D_{\text{div}}^{is} = \langle \phi_w^i, \text{div } \phi_\gamma^s \rangle_{L^2(\Omega)}, \quad D_{\text{Div}}^{mq} = \langle \phi_\theta^m, \text{Div } \Phi_\kappa^q \rangle_{L^2(\Omega, \mathbb{R}^2)}. \quad (7.101)$$

Matrix \mathbf{B}_{q_n} , $\mathbf{B}_{M_{nn}}$, $\mathbf{B}_{M_{ns}}$ are computed as ($l \in \{1, n_\partial\}$)

$$B_{q_n}^{rl} = \left\langle \gamma_n \phi_\gamma^r, \phi_{\partial,1}^l \right\rangle_{L^2(\partial\Omega)}, \quad B_{M_{nn}}^{pl} = \left\langle \gamma_{nn} \Phi_\kappa^p, \phi_{\partial,2}^l \right\rangle_{L^2(\partial\Omega)}, \quad B_{M_{ns}}^{pl} = \left\langle \gamma_{ns} \Phi_\kappa^p, \phi_{\partial,3}^l \right\rangle_{L^2(\partial\Omega)}. \quad (7.102)$$

This finite dimensional system represents a purely mixed discretization of the problem and is really close to the plane elasticity system. Conforming finite elements for the plane elasticity system on simplicial meshes have been constructed in [AW02]. The resulting element is rather cumbersome and computationally expensive as the stress tensor has at least 24 degrees of freedom on a triangle. For this reason, many finite element discretization imposes the symmetry of the stress tensor weakly [AFW07]. To actually implement the discretization, in Chap. 8 the Mindlin plate problem is going to be reformulated so that the momenta tensor is only weakly symmetric.

7.2 Mixed boundary conditions

In this section Assumption 3 on uniform boundary condition is modified to account for general non homogeneous boundary conditions. The discretization of Stokes-Dirac structure under mixed causality has been already treated in [KML18]. However, to satisfy the power balance at a discrete level, some additional parameters are introduced. This makes the employment of this methodology not simple and dependent on the considered application. Furthermore, elasticity models do not fall within the required assumptions.

We propose here two methodologies to tackle mixed boundary conditions within the Partitioned Finite Element Method. The first introduces Lagrange multipliers, and therefore algebraic constraints, to enforce the mixed causality. Finite dimensional differential algebraic port-Hamiltonian systems (pHDAE) have been introduced in [BMXZ18] for linear systems and in [MM19] for non linear systems. This enriched description share all the crucial features of ordinary pHs, but easily account for algebraic constraints, time-dependent transformations and explicit dependence on time in the Hamiltonian. The second method employs a domain decomposition technique to interconnect systems with different causalities. For the sake of simplicity The illustration is restrained to the linear case.

The open connected set $\Omega \subset \mathbb{R}^d$, $d = \{1, 2, 3\}$, with Lipschitz boundary $\partial\Omega$ represent the spatial domain. The boundary is split into two partition $\partial\Omega = \bar{\Gamma}_1 \cup \bar{\Gamma}_2$, $\Gamma_1 \cap \Gamma_2 = \{\emptyset\}$. The set Γ_1 , Γ_2 are considered to be connected, cf. Fig. 7.1.

Remark 10 (Connectedness of Γ_1, Γ_2)

Disconnected set can be handled as well. This requires the introduction of an heavy notation and complicates the illustration. For sake of simplicity, the connectedness hypothesis applies.

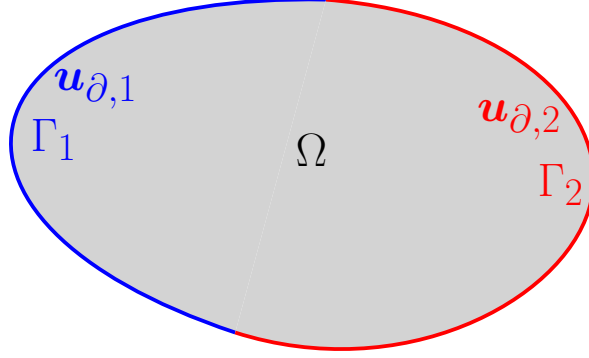


Figure 7.1: Partition of boundary into two connected sets.

1361 For scalars $a_{\partial,*}, b_{\partial,*} \in L^2(\Gamma_*)$ and vectors $\mathbf{a}_{\partial,*}, \mathbf{b}_{\partial,*} \in L^2(\Gamma_*, \mathbb{R}^m)$ defined on the boundary
 1362 partition Γ_* the inner product is defined as

$$\langle a_{\partial,*}, b_{\partial,*} \rangle_{L^2(\Gamma_*)} = \int_{\Gamma_*} a_{\partial,*} b_{\partial,*} \, d\Gamma_*, \quad \langle \mathbf{a}_{\partial,*}, \mathbf{b}_{\partial,*} \rangle_{L^2(\Gamma_*, \mathbb{R}^m)} = \int_{\Gamma_*} \mathbf{a}_{\partial,*} \cdot \mathbf{b}_{\partial,*} \, d\Gamma_*. \quad (7.103)$$

Consider now the following boundary control linear pH system in co-energy form

$$\begin{bmatrix} \mathcal{M}_1 & 0 \\ 0 & \mathcal{M}_2 \end{bmatrix} \partial_t \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix} = \begin{bmatrix} 0 & -\mathbf{L}^\top - \mathcal{L}^* \\ \mathbf{L} + \mathcal{L} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{matrix} \mathbf{e}_1 \in H^\mathcal{L}, \\ \mathbf{e}_2 \in H^{-\mathcal{L}*}, \end{matrix} \quad (7.104a)$$

$$\begin{pmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,2} \end{pmatrix} = \begin{bmatrix} \mathcal{N}_{\partial,1}^{\Gamma_1} & 0 \\ 0 & \mathcal{N}_{\partial,2}^{\Gamma_2} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{matrix} \mathbf{u}_{\partial,1} \in \mathbb{R}^m, \\ \mathbf{u}_{\partial,2} \in \mathbb{R}^m, \end{matrix} \quad (7.104b)$$

$$\begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,2} \end{pmatrix} = \begin{bmatrix} 0 & \mathcal{N}_{\partial,2}^{\Gamma_1} \\ \mathcal{N}_{\partial,1}^{\Gamma_2} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{matrix} \mathbf{y}_{\partial,1} \in \mathbb{R}^m, \\ \mathbf{y}_{\partial,2} \in \mathbb{R}^m. \end{matrix} \quad (7.104c)$$

1363 The operator $\mathcal{N}_{\partial,*}^{\Gamma_\circ}$ with $*, \circ \in \{1, 2\}$ represent now the restriction of operator $\mathcal{N}_{\partial,*}$, defined
 1364 in Eq. (7.8), over the subset Γ_\circ . The boundary inputs and output are now vectors \mathbb{R}^{2m} . This
 1365 does not mean that the boundary conditions have been doubled, but only that the components
 1366 of $\mathbf{u}_\partial, \mathbf{y}_\partial$ are only defined on the subsets Γ_1, Γ_2 of the overall boundary. This corresponds to
 1367 a slight modification of Assumption 3.

1368 Given the additive property of the integral, it is possible to write

$$\begin{aligned} \langle \mathcal{N}_{\partial,1} \mathbf{e}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{e}_1, \mathcal{N}_{\partial,2}^{\Gamma_1} \mathbf{e}_2 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{e}_1, \mathcal{N}_{\partial,2}^{\Gamma_2} \mathbf{e}_2 \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \\ &= \langle \mathbf{u}_{\partial,1}, \mathbf{y}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathbf{y}_{\partial,2}, \mathbf{u}_{\partial,2} \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}. \end{aligned} \quad (7.105)$$

1369 The continuous power balance is obtained using Eqs. (7.50) and (7.105)

$$\dot{H} = \langle \mathbf{u}_{\partial,1}, \mathbf{y}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathbf{y}_{\partial,2}, \mathbf{u}_{\partial,2} \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}. \quad (7.106)$$

7.2.1 Solution using Lagrange multipliers

This solution introduces a Lagrange multiplier for the boundary control that does not arise explicitly in the weak form. To illustrate the idea, consider again the weak form 7.51 (obtained by integration by parts of the $-\mathcal{L}^*$ partition) of Sys. 7.104

$$\begin{aligned}\langle \mathbf{v}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{A})} - \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}, \\ \langle \mathbf{v}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega, \mathbb{B})}.\end{aligned}\tag{7.107}$$

The term $\langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)}$ can be split into the two boundary contributions, as in Eq. (7.105). The variable $\mathbf{y}_{\partial,1}$ plays here the role of a Lagrange multiplier $\mathbf{y}_{\partial,1} = \boldsymbol{\lambda}_{\partial,1}$

$$\begin{aligned}\langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega, \mathbb{R}^m)} &= \langle \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{v}_1, \mathcal{N}_{\partial,2}^{\Gamma_1} \mathbf{e}_2 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{v}_1, \mathcal{N}_{\partial,2}^{\Gamma_2} \mathbf{e}_2 \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \\ &= \langle \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{v}_1, \mathbf{y}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{v}_1, \mathbf{u}_{\partial,2} \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \\ &= \langle \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{v}_1, \boldsymbol{\lambda}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{v}_1, \mathbf{u}_{\partial,2} \rangle_{L^2(\Gamma_2, \mathbb{R}^m)},\end{aligned}\tag{7.108}$$

If test function $\mathbf{v}_{\partial,1}, \mathbf{v}_{\partial,2} \in \mathbb{R}^m$ are introduced, the input and outputs definitions

$$\mathbf{u}_{\partial,1} = \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{e}_1, \quad \mathbf{y}_{\partial,1} = \boldsymbol{\lambda}_{\partial,1}, \quad \mathbf{y}_{\partial,2} = \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{e}_1,\tag{7.109}$$

can be put into weak form to obtain

$$\begin{aligned}\langle \mathbf{v}_{\partial,1}, \mathbf{u}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} &= \langle \mathbf{v}_{\partial,1}, \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{e}_1 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, \\ \langle \mathbf{v}_{\partial,1}, \mathbf{y}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} &= \langle \mathbf{v}_{\partial,1}, \boldsymbol{\lambda}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, \\ \langle \mathbf{v}_{\partial,2}, \mathbf{y}_{\partial,2} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} &= \langle \mathbf{v}_{\partial,2}, \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{e}_1 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}.\end{aligned}\tag{7.110}$$

As usual, a Galerkin approximation is introduced

$$\begin{aligned}\mathbf{v}_1 &\approx \sum_{i=1}^{n_1} \phi_1^i(\mathbf{x}) v_1^i, & \mathbf{e}_1 &\approx \sum_{i=1}^{n_1} \phi_1^i(\mathbf{x}) e_1^i(t), & \Delta_{\partial,1} &\approx \sum_{i=1}^{n_{\partial,1}} \phi_{\partial,1}^i(\mathbf{s}_1) \Delta_{\partial,1}^i, & \mathbf{s}_1 &\in \Gamma_1, \\ \mathbf{v}_2 &\approx \sum_{i=1}^{n_2} \phi_2^i(\mathbf{x}) v_2^i, & \mathbf{e}_2 &\approx \sum_{i=1}^{n_2} \phi_2^i(\mathbf{x}) e_2^i(t), & \square_{\partial,2} &\approx \sum_{i=1}^{n_{\partial,2}} \phi_{\partial,2}^i(\mathbf{s}_2) \square_{\partial,2}^i(t), & \mathbf{s}_2 &\in \Gamma_2.\end{aligned}\tag{7.111}$$

where \triangle stays for v, u, y, λ and \square for v, u, y . Replacing the approximation 7.111 into Eqs. 7.107, 7.108, 7.110, the following differential-algebraic system is constructed

$$\begin{aligned} \text{Diag} \begin{bmatrix} \mathbf{M}_{\mathcal{M}_1} \\ \mathbf{M}_{\mathcal{M}_2} \\ \mathbf{0} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_1 \\ \dot{\mathbf{e}}_2 \\ \dot{\boldsymbol{\lambda}}_{\partial,1} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top - \mathbf{D}_{\mathcal{L}}^\top & \mathbf{B}_{1,\Gamma_1} \\ \mathbf{D}_0 + \mathbf{D}_{\mathcal{L}} & \mathbf{0} & \mathbf{0} \\ -\mathbf{B}_{1,\Gamma_1}^\top & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \\ \boldsymbol{\lambda}_{\partial,1} \end{pmatrix} + \begin{bmatrix} \mathbf{0} & \mathbf{B}_{1,\Gamma_2} \\ \mathbf{0} & \mathbf{0} \\ \mathbf{M}_{\partial,1} & \mathbf{0} \end{bmatrix} \begin{bmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,2} \end{bmatrix}, \\ \begin{bmatrix} \mathbf{M}_{\partial,1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,2} \end{bmatrix} \begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{0} & \mathbf{M}_{\partial,1} \\ \mathbf{B}_{1,\Gamma_2}^\top & \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \\ \boldsymbol{\lambda}_{\partial,1} \end{pmatrix}. \end{aligned} \quad (7.112)$$

Apart for matrices $\mathbf{M}_{\partial,1}, \mathbf{M}_{\partial,2}, \mathbf{B}_{1,\Gamma_1}, \mathbf{B}_{1,\Gamma_2}$,

$$\begin{aligned} M_{\partial,1}^{lk} &= \langle \phi_{\partial,1}^l, \phi_{\partial,1}^k \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, \quad (l, k) \in \{1, n_{\partial,1}\}, \quad B_{1,\Gamma_1}^{ik} = \langle \mathcal{N}_{\partial,1}^{\Gamma_1} \phi_1^i, \phi_{\partial,1}^k \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, \quad i \in \{1, n_1\}, \\ M_{\partial,2}^{fg} &= \langle \phi_{\partial,2}^f, \phi_{\partial,2}^g \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \quad (f, g) \in \{1, n_{\partial,2}\}, \quad B_{1,\Gamma_2}^{ig} = \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \phi_1^i, \phi_{\partial,2}^g \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \end{aligned} \quad (7.113)$$

the other matrices keep the same definition as in (7.53). The discrete Hamiltonian, whose expression is [BMXZ18]

$$H_d = \frac{1}{2} \mathbf{e}_1^\top \mathbf{M}_{\mathcal{M}_1} \mathbf{e}_1 + \frac{1}{2} \mathbf{e}_2^\top \mathbf{M}_{\mathcal{M}_2} \mathbf{e}_2. \quad (7.114)$$

gives rise to the discrete power balance

$$\begin{aligned} \dot{H}_d &= \mathbf{e}_1^\top \mathbf{M}_{\mathcal{M}_1} \dot{\mathbf{e}}_1 + \mathbf{e}_2^\top \mathbf{M}_{\mathcal{M}_2} \dot{\mathbf{e}}_2, \\ &= -\mathbf{e}_1^\top (\mathbf{D}_0 + \mathbf{D}_{\mathcal{L}})^\top \mathbf{e}_2 + \mathbf{e}_2^\top (\mathbf{D}_0 + \mathbf{D}_{\mathcal{L}}) \mathbf{e}_1 + \mathbf{e}_1^\top (\mathbf{B}_{1,\Gamma_1} \boldsymbol{\lambda}_{\partial,1} + \mathbf{B}_{1,\Gamma_2} \mathbf{u}_{\partial,2}), \\ &= \mathbf{y}_{\partial,1}^\top \mathbf{M}_{\partial,1} \mathbf{u}_{\partial,1} + \mathbf{y}_{\partial,2}^\top \mathbf{M}_{\partial,2} \mathbf{u}_{\partial,2}, \\ &= \hat{\mathbf{y}}_{\partial,1}^\top \mathbf{u}_{\partial,1} + \hat{\mathbf{y}}_{\partial,2}^\top \mathbf{u}_{\partial,2}, \quad \text{where} \quad \hat{\mathbf{y}}_{\partial,1} := \mathbf{M}_{\partial,1} \mathbf{y}_{\partial,1}, \quad \hat{\mathbf{y}}_{\partial,2} := \mathbf{M}_{\partial,2} \mathbf{y}_{\partial,2}. \end{aligned} \quad (7.115)$$

This result is the finite dimensional equivalent of (7.106).

Equivalently, the weak form Eq. 7.52 may be used as a starting point. The computation follows in a completely analogous manner. The only difference is that $\mathbf{y}_{\partial,2} = \boldsymbol{\lambda}_{\partial,2}$ plays the role of the Lagrange multiplier. The final finite dimensional system then is given by

$$\begin{aligned} \text{Diag} \begin{bmatrix} \mathbf{M}_{\mathcal{M}_1} \\ \mathbf{M}_{\mathcal{M}_2} \\ \mathbf{0} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_1 \\ \dot{\mathbf{e}}_2 \\ \dot{\boldsymbol{\lambda}}_{\partial,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^\top + \mathbf{D}_{-\mathcal{L}}^* & \mathbf{0} \\ \mathbf{D}_0 - \mathbf{D}_{-\mathcal{L}}^* & \mathbf{0} & \mathbf{B}_{2,\Gamma_2} \\ \mathbf{0} & -\mathbf{B}_{2,\Gamma_2}^\top & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \\ \boldsymbol{\lambda}_{\partial,2} \end{pmatrix} + \begin{bmatrix} \mathbf{0} & \mathbf{0} \\ \mathbf{B}_{2,\Gamma_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,2} \end{bmatrix} \begin{bmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,2} \end{bmatrix}, \\ \begin{bmatrix} \mathbf{M}_{\partial,1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,2} \end{bmatrix} \begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{B}_{2,\Gamma_1}^\top & \mathbf{0} \\ \mathbf{0} & \mathbf{0} & \mathbf{M}_{\partial,2} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \\ \boldsymbol{\lambda}_{\partial,2} \end{pmatrix}. \end{aligned} \quad (7.116)$$

where $\mathbf{B}_{2,\Gamma_1}, \mathbf{B}_{2,\Gamma_2}$ are given by

$$B_{2,\Gamma_1}^{mk} = \langle \mathcal{N}_{\partial,2}^{\Gamma_1} \phi_2^m, \phi_{\partial,1}^k \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, \quad B_{2,\Gamma_2}^{mg} = \langle \mathcal{N}_{\partial,2}^{\Gamma_2} \phi_2^m, \phi_{\partial,2}^g \rangle_{L^2(\Gamma_2, \mathbb{R}^m)}, \quad (7.117)$$

where $m \in \{1, n_2\}, k \in \{1, n_{\partial,1}\}, g \in \{1, n_{\partial,2}\}$. This solution can be applied to incorporate

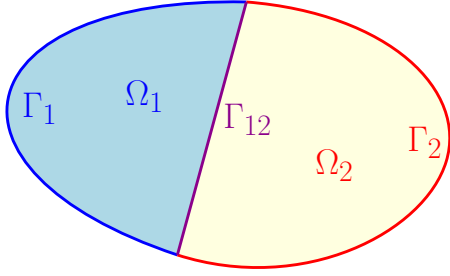
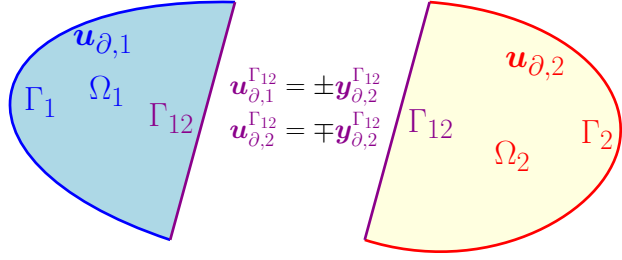


Figure 7.2: Splitting of the domain.

Figure 7.3: Interconnection at the interface Γ_{12} .

all possible mixed boundary conditions in a systematic manner. However the finite element discretization is required to satisfy the inf-sup condition. Simulating the resulting system is harder, since the algebraic constraints pose additional difficulties for the time integration.

7.2.2 Virtual domain decomposition

Since the boundary subsets Γ_1 , Γ_2 are supposed to be connected set, a single interface is sufficient to decompose the system appropriately. In Fig. 7.2 the splitting of the domain is accomplished by introducing the interface Γ_{12} . This separation line that separates the domain is an additional degree of freedom, as it can be freely drawn. If the finite element method is used for the basis functions, the interface should be drawn so that the meshing of the subdomains does not generate excessively skewed triangles.

The idea is based on the fact that System 7.104 can be split into two systems with uniform causality. The following set of boundary variables is used for Ω_1 subdomain

$$\begin{pmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,1}^{\Gamma_{12}} \end{pmatrix} = \begin{bmatrix} \mathcal{N}_{\partial,1}^{\Gamma_1} & 0 \\ \mathcal{N}_{\partial,1}^{\Gamma_{12}} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,1}^{\Gamma_{12}} \end{pmatrix} = \begin{bmatrix} 0 & \mathcal{N}_{\partial,2}^{\Gamma_1} \\ 0 & \mathcal{N}_{\partial,2}^{\Gamma_{12}} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}. \quad (7.118)$$

Whereas for the Ω_2 subdomain, the boundary variables are

$$\begin{pmatrix} \mathbf{u}_{\partial,2} \\ \mathbf{u}_{\partial,2}^{\Gamma_{12}} \end{pmatrix} = \begin{bmatrix} 0 & \mathcal{N}_{\partial,2}^{\Gamma_2} \\ 0 & \mathcal{N}_{\partial,2}^{\Gamma_{12}} \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}, \quad \begin{pmatrix} \mathbf{y}_{\partial,2} \\ \mathbf{y}_{\partial,2}^{\Gamma_{12}} \end{pmatrix} = \begin{bmatrix} \mathcal{N}_{\partial,1}^{\Gamma_1} & 0 \\ \mathcal{N}_{\partial,1}^{\Gamma_{12}} & 0 \end{bmatrix} \begin{pmatrix} \mathbf{e}_1 \\ \mathbf{e}_2 \end{pmatrix}. \quad (7.119)$$

The following relations then hold (cf. Fig. 7.3)

$$\mathbf{u}_{\partial,1}^{\Gamma_{12}} = \pm \mathbf{y}_{\partial,2}^{\Gamma_{12}}, \quad \mathbf{u}_{\partial,2}^{\Gamma_{12}} = \mp \mathbf{y}_{\partial,1}^{\Gamma_{12}}. \quad (7.120)$$

The plus or minus sign is due to the fact that either $\mathcal{N}_{\partial,1}^{\Gamma_{12}}$ or $\mathcal{N}_{\partial,2}^{\Gamma_{12}}$ contains a scalar product with the outgoing normal (or the tangent unit vector) at Γ_{12} (that has opposite direction depending on which subdomain is considered). These relations are at the core of the methodology, since they state the equivalence between a problem with mixed causalities and the interconnection of two problems with uniform causality.

1411 To obtain a final system with the desired causality, the weak form has to be carried out
 1412 separately on each subdomain. In particular, on subdomain Ω_1 the \mathcal{L} operator is integrated
 1413 by parts, whereas on subdomain Ω_2 the $-\mathcal{L}^*$ operator undergoes the integration by parts.
 1414 Consequently, on subdomains Ω_1 (Ω_2) the boundary input $\mathbf{u}_{\partial,1}$ ($\mathbf{u}_{\partial,2}$) explicitly appears. Let
 1415 $L^2(\Omega_*, \mathbb{A})$ be the L^2 space restricted to the subdomain Ω_* , and let $L^2(\Omega_*, \mathbb{B})$ be the restriction
 1416 of the L^2 space to Ω_* for $* \in \{1, 2\}$. The weak form of the dynamics (7.104a) for the Ω_1
 1417 contribution reads

$$\begin{aligned} \langle \mathbf{v}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega_1, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega_1, \mathbb{A})} - \langle \mathbf{v}_1, \mathcal{L}^* \mathbf{e}_2 \rangle_{L^2(\Omega_1, \mathbb{A})} \\ \langle \mathbf{v}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega_1, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega_1, \mathbb{B})} + \langle \mathcal{L}^* \mathbf{v}_2, \mathbf{e}_1 \rangle_{L^2(\Omega_1, \mathbb{A})} + \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\partial\Omega_1, \mathbb{R}^m)}. \end{aligned} \quad (7.121)$$

1418 For Ω_2 , we get

$$\begin{aligned} \langle \mathbf{v}_1, \mathcal{M}_1 \partial_t \mathbf{e}_1 \rangle_{L^2(\Omega_2, \mathbb{A})} &= -\langle \mathbf{v}_1, \mathbf{L}^\top \mathbf{e}_2 \rangle_{L^2(\Omega_2, \mathbb{A})} - \langle \mathcal{L} \mathbf{v}_1, \mathbf{e}_2 \rangle_{L^2(\Omega_2, \mathbb{B})} + \langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega_2, \mathbb{R}^m)}, \\ \langle \mathbf{v}_2, \mathcal{M}_2 \partial_t \mathbf{e}_2 \rangle_{L^2(\Omega_2, \mathbb{B})} &= \langle \mathbf{v}_2, \mathbf{L} \mathbf{e}_1 \rangle_{L^2(\Omega_2, \mathbb{B})} + \langle \mathbf{v}_2, \mathcal{L} \mathbf{e}_1 \rangle_{L^2(\Omega_2, \mathbb{B})}. \end{aligned} \quad (7.122)$$

1419 Since $\partial\Omega_1 = \bar{\Gamma}_1 \cup \bar{\Gamma}_{12}$ and $\partial\Omega_2 = \bar{\Gamma}_2 \cup \bar{\Gamma}_{12}$, the boundary terms can be decomposed

$$\begin{aligned} \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\partial\Omega_1, \mathbb{R}^m)} &= \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,2} \mathbf{v}_2, \mathcal{N}_{\partial,1} \mathbf{e}_1 \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}, \\ &= \langle \mathcal{N}_{\partial,2}^{\Gamma_1} \mathbf{v}_2, \mathcal{N}_{\partial,1}^{\Gamma_1} \mathbf{e}_1 \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,2}^{\Gamma_{12}} \mathbf{v}_2, \mathcal{N}_{\partial,1}^{\Gamma_{12}} \mathbf{e}_1 \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}, \\ &= \langle \mathcal{N}_{\partial,2}^{\Gamma_1} \mathbf{v}_2, \mathbf{u}_{\partial,1} \rangle_{L^2(\Gamma_1, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,2}^{\Gamma_{12}} \mathbf{v}_2, \mathbf{u}_{\partial,1}^{\Gamma_{12}} \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}. \end{aligned} \quad (7.123)$$

1420 Analogously, for the remaining boundary term we find

$$\langle \mathcal{N}_{\partial,1} \mathbf{v}_1, \mathcal{N}_{\partial,2} \mathbf{e}_2 \rangle_{L^2(\partial\Omega_2, \mathbb{R}^m)} = \langle \mathcal{N}_{\partial,1}^{\Gamma_2} \mathbf{v}_1, \mathbf{u}_{\partial,2} \rangle_{L^2(\Gamma_2, \mathbb{R}^m)} + \langle \mathcal{N}_{\partial,1}^{\Gamma_{12}} \mathbf{v}_1, \mathbf{u}_{\partial,2}^{\Gamma_{12}} \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}. \quad (7.124)$$

1421 A Galerkin approximation, analogous to (7.111), is used for each subdomain

$$\begin{aligned} \mathbf{v}_{1,1} &\approx \sum_{i=1}^{n_{1,1}} \phi_{1,1}^i(\mathbf{x}_1) v_{1,1}^i, & \mathbf{x}_1 \in \Omega_1, & \quad \mathbf{v}_{1,2} \approx \sum_{i=1}^{n_{1,2}} \phi_{1,2}^i(\mathbf{x}_2) v_{1,2}^i, & \mathbf{x}_2 \in \Omega_2, \\ \mathbf{v}_{2,1} &\approx \sum_{i=1}^{n_{2,1}} \phi_{2,1}^i(\mathbf{x}_1) v_{2,1}^i, & & \quad \mathbf{v}_{2,2} \approx \sum_{i=1}^{n_{2,2}} \phi_{2,2}^i(\mathbf{x}_2) v_{2,2}^i, & \\ \mathbf{e}_{1,1} &\approx \sum_{i=1}^{n_{1,1}} \phi_{1,1}^i(\mathbf{x}_1) e_{1,1}^i(t), & & \quad \mathbf{e}_{1,2} \approx \sum_{i=1}^{n_{1,2}} \phi_{1,2}^i(\mathbf{x}_2) e_{1,2}^i(t), & \\ \mathbf{e}_{2,1} &\approx \sum_{i=1}^{n_{2,1}} \phi_{2,1}^i(\mathbf{x}_1) e_{2,1}^i(t), & & \quad \mathbf{e}_{2,2} \approx \sum_{i=1}^{n_{2,2}} \phi_{2,2}^i(\mathbf{x}_2) e_{2,2}^i(t). & \end{aligned} \quad (7.125)$$

For the boundary variables, additional terms for the common interface are needed

$$\begin{aligned} \square_{\partial,1} &\approx \sum_{i=1}^{n_{\partial,1}} \phi_{\partial,1}^i(\mathbf{s}_1) \square_{\partial,1}^i(t), \quad \mathbf{s}_1 \in \Gamma_1, & \square_{\partial,1}^{\Gamma_{12}} &\approx \sum_{i=1}^{n_{\partial,12}} \phi_{\partial,12}^i(\mathbf{s}_{12}) \square_{\partial,1}^{i,\Gamma_{12}}(t), \\ & & & \mathbf{s}_{12} \in \Gamma_{12}. \\ \square_{\partial,2} &\approx \sum_{i=1}^{n_{\partial,2}} \phi_{\partial,2}^i(\mathbf{s}_2) \square_{\partial,2}^i(t), \quad \mathbf{s}_2 \in \Gamma_2, & \square_{\partial,2}^{\Gamma_{12}} &\approx \sum_{i=1}^{n_{\partial,12}} \phi_{\partial,12}^i(\mathbf{s}_{12}) \square_{\partial,2}^{i,\Gamma_{12}}(t), \end{aligned} \quad (7.126)$$

where \square stays for v, u, y .

Remark 11 (Choice of the interface basis functions)

Notice that the same basis functions $\phi_{\partial,12}$ are used for both interface variables. This is necessary in order to dispose of the same degrees of freedom for the interconnection.

Replacing approximations 7.111, 7.126 into Eqs. 7.121, 7.123, 7.118, a finite dimensional system for the Ω_1 subdomain is obtained

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\mathcal{M}_1}^{\Omega_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\mathcal{M}_2}^{\Omega_1} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_{1,1} \\ \dot{\mathbf{e}}_{2,1} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^{\Omega_1 \top} + \mathbf{D}_{-\mathcal{L}^*}^{\Omega_1} \\ \mathbf{D}_0^{\Omega_1} - \mathbf{D}_{-\mathcal{L}^*}^{\Omega_1 \top} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{1,1} \\ \mathbf{e}_{2,1} \end{pmatrix} + \begin{bmatrix} \mathbf{0} & \mathbf{0} \\ \mathbf{B}_{2,\Gamma_1}^{\Omega_1} & \mathbf{B}_{2,\Gamma_{12}}^{\Omega_1} \end{bmatrix} \begin{pmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,1}^{\Gamma_{12}} \end{pmatrix}, \\ \begin{bmatrix} \mathbf{M}_{\partial,1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,12} \end{bmatrix} \begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,1}^{\Gamma_{12}} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & \mathbf{B}_{2,\Gamma_1}^{\Omega_1 \top} \\ \mathbf{0} & \mathbf{B}_{2,\Gamma_{12}}^{\Omega_1 \top} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{1,1} \\ \mathbf{e}_{2,1} \end{pmatrix}. \end{aligned} \quad (7.127)$$

The mass and interconnection operator matrices are the restriction to the subdomain of the matrices given in (7.116)

$$\begin{aligned} M_{\mathcal{M}_1}^{\Omega_1,ij} &= \langle \phi_{1,1}^i, \mathcal{M}_1 \phi_{1,1}^j \rangle_{L^2(\Omega_1, \mathbb{A})}, & D_0^{\Omega_1,mj} &= \langle \phi_{2,1}^i, \mathbf{L} \phi_{1,1}^j \rangle_{L^2(\Omega_1, \mathbb{B})}, & i, j &\in \{1, n_{1,1}\}, \\ M_{\mathcal{M}_2}^{\Omega_1,mn} &= \langle \phi_{2,1}^m, \mathcal{M}_2 \phi_{2,1}^n \rangle_{L^2(\Omega_1, \mathbb{B})}, & D_{-\mathcal{L}^*}^{\Omega_1,in} &= \langle \phi_{1,1}^m, -\mathcal{L}^* \phi_{2,1}^n \rangle_{L^2(\Omega_1, \mathbb{A})}, & m, n &\in \{1, n_{2,1}\}. \end{aligned} \quad (7.128)$$

Matrices $\mathbf{M}_{\partial,1}$ is constructed as in Eq. (7.116). Matrix $\mathbf{M}_{\partial,12}$ is similarly built

$$M_{\partial,12}^{lk} = \langle \phi_{\partial,12}^l, \phi_{\partial,12}^k \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}, \quad l, k \in \{1, n_{\partial,12}\}. \quad (7.129)$$

The novel matrices $\mathbf{B}_{2,\Gamma_1}^{\Omega_1}, \mathbf{B}_{1,\Gamma_{12}}^{\Omega_1}$ have elements

$$\begin{aligned} B_{2,\Gamma_1}^{\Omega_1,mh} &= \langle \mathcal{N}_{\partial,2}^{\Gamma_1} \phi_{2,1}^m, \phi_{\partial,1}^h \rangle_{L^2(\Gamma_1, \mathbb{R}^m)}, & m &\in \{1, n_{2,1}\}, & h &\in \{1, n_{\partial,1}\}, \\ B_{2,\Gamma_{12}}^{\Omega_1,mk} &= \langle \mathcal{N}_{\partial,2}^{\Gamma_{12}} \phi_{2,1}^m, \phi_{\partial,12}^k \rangle_{L^2(\Gamma_{12}, \mathbb{R}^m)}, & & & k &\in \{1, n_{\partial,12}\}. \end{aligned} \quad (7.130)$$

If instead the approximations are plugged into Eqs. 7.122, 7.124, 7.119, a finite dimensional system for the Ω_2 subdomain is computed

$$\begin{aligned}
\begin{bmatrix} \mathbf{M}_{\mathcal{M}_1}^{\Omega_2} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\mathcal{M}_2}^{\Omega_2} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_{1,2} \\ \dot{\mathbf{e}}_{2,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{0} & -\mathbf{D}_0^{\Omega_2 \top} - \mathbf{D}_{\mathcal{L}}^{\Omega_2 \top} \\ \mathbf{D}_0^{\Omega_2} + \mathbf{D}_{\mathcal{L}}^{\Omega_2} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{1,2} \\ \mathbf{e}_{2,2} \end{pmatrix} + \begin{bmatrix} \mathbf{B}_{1,\Gamma_2}^{\Omega_2} & \mathbf{B}_{1,\Gamma_{12}}^{\Omega_2} \\ \mathbf{0} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{u}_{\partial,2} \\ \mathbf{u}_{\partial,2}^{\Gamma_{12}} \end{pmatrix}, \\
\begin{bmatrix} \mathbf{M}_{\partial,2} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,12} \end{bmatrix} \begin{pmatrix} \mathbf{y}_{\partial,2} \\ \mathbf{y}_{\partial,2}^{\Gamma_{12}} \end{pmatrix} &= \begin{bmatrix} \mathbf{B}_{1,\Gamma_2}^{\Omega_2 \top} & \mathbf{0} \\ \mathbf{B}_{1,\Gamma_{12}}^{\Omega_2 \top} & \mathbf{0} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{1,2} \\ \mathbf{e}_{2,2} \end{pmatrix}.
\end{aligned} \tag{7.131}$$

1435 The mass and interconnection operator matrices are the restriction to the subdomain of
 1436 the matrices given in (7.112)

$$\begin{aligned}
M_{\mathcal{M}_1}^{\Omega_2,ij} &= \left\langle \phi_{1,2}^i, \mathcal{M}_1 \phi_{1,2}^j \right\rangle_{L^2(\Omega_2, \mathbb{A})}, \quad D_0^{\Omega_2,mj} = \left\langle \phi_{2,2}^i, \mathbf{L} \phi_{1,2}^j \right\rangle_{L^2(\Omega_2, \mathbb{B})}, \quad i, j \in \{1, n_{1,2}\}, \\
M_{\mathcal{M}_2}^{\Omega_2,mn} &= \left\langle \phi_{2,2}^m, \mathcal{M}_2 \phi_{2,2}^n \right\rangle_{L^2(\Omega_2, \mathbb{B})}, \quad D_{\mathcal{L}}^{\Omega_2,mj} = \left\langle \phi_{2,2}^m, \mathcal{L} \phi_{1,2}^j \right\rangle_{L^2(\Omega_2, \mathbb{B})}, \quad m, n \in \{1, n_{2,2}\}.
\end{aligned} \tag{7.132}$$

1437 Matrix $\mathbf{M}_{\partial,2}$ is constructed as in (7.112). The elements of matrices \mathbf{B}_{1,Γ_2} , $\mathbf{B}_{1,\Gamma_{12}}$ are computed
 1438 as

$$\begin{aligned}
B_{1,\Gamma_2}^{ig} &= \left\langle \mathcal{N}_{\partial,1}^{\Gamma_2} \phi_{1,2}^i, \phi_{\partial,2}^g \right\rangle_{L^2(\Gamma_2)}, \quad i \in \{1, n_{1,2}\}, \quad g \in \{1, n_{\partial,2}\}, \\
B_{1,\Gamma_{12}}^{ik} &= \left\langle \mathcal{N}_{\partial,1}^{\Gamma_{12}} \phi_{1,2}^i, \phi_{\partial,12}^k \right\rangle_{L^2(\Gamma_{12})}, \quad k \in \{1, n_{\partial,12}\}.
\end{aligned} \tag{7.133}$$

1439 Systems (7.127), (7.131) are compactly rewritten as

System (7.127)	System (7.131)
$ \begin{aligned} \mathbf{M}_{\Omega_1} \dot{\mathbf{e}}_{\Omega_1} &= \mathbf{J}_{\Omega_1} \mathbf{e}_{\Omega_1} + \mathbf{B}_{\Gamma_1}^{\Omega_1} \mathbf{u}_{\partial,1} + \mathbf{B}_{\Gamma_{12}}^{\Omega_1} \mathbf{u}_{\partial,1}^{\Gamma_{12}}, \\ \mathbf{M}_{\partial,1} \mathbf{y}_{\partial,1} &= \mathbf{B}_{\Gamma_1}^{\Omega_1 \top} \mathbf{e}_{\Omega_1}, \\ \mathbf{M}_{\partial,12} \mathbf{y}_{\partial,1}^{\Gamma_{12}} &= \mathbf{B}_{\Gamma_{12}}^{\Omega_1 \top} \mathbf{e}_{\Omega_1}. \end{aligned} \tag{7.134} $ <p>with Hamiltonian $H_{d,1} = \frac{1}{2} \mathbf{e}_{\Omega_1}^\top \mathbf{M}_{\Omega_1} \mathbf{e}_{\Omega_1}$</p>	$ \begin{aligned} \mathbf{M}_{\Omega_2} \dot{\mathbf{e}}_{\Omega_2} &= \mathbf{J}_{\Omega_2} \mathbf{e}_{\Omega_2} + \mathbf{B}_{\Gamma_2}^{\Omega_2} \mathbf{u}_{\partial,2} + \mathbf{B}_{\Gamma_{12}}^{\Omega_2} \mathbf{u}_{\partial,2}^{\Gamma_{12}}, \\ \mathbf{M}_{\partial,2} \mathbf{y}_{\partial,2} &= \mathbf{B}_{\Gamma_2}^{\Omega_2 \top} \mathbf{e}_{\Omega_2}, \\ \mathbf{M}_{\partial,12} \mathbf{y}_{\partial,2}^{\Gamma_{12}} &= \mathbf{B}_{\Gamma_{12}}^{\Omega_2 \top} \mathbf{e}_{\Omega_2}. \end{aligned} \tag{7.135} $ <p>with Hamiltonian $H_{d,2} = \frac{1}{2} \mathbf{e}_{\Omega_2}^\top \mathbf{M}_{\Omega_2} \mathbf{e}_{\Omega_2}$</p>

1441 To obtain a system with the desired causality, an interconnection is employed to connect
 1442 the two Systems (7.134), (7.135) along the shared boundary Γ_{12} . Given (7.120), the gyrator
 1443 interconnection is computed as

$$\begin{aligned}
\mathbf{u}_{\partial,1}^{\Gamma_{12}} &= \pm \mathbf{y}_{\partial,2}^{\Gamma_{12}} = \pm \mathbf{M}_{\partial,12}^{-1} \mathbf{B}_{\Gamma_{12}}^{\Omega_2 \top} \mathbf{e}_{\Omega_2}, \\
\mathbf{u}_{\partial,2}^{\Gamma_{12}} &= \mp \mathbf{y}_{\partial,1}^{\Gamma_{12}} = \mp \mathbf{M}_{\partial,12}^{-1} \mathbf{B}_{\Gamma_{12}}^{\Omega_1 \top} \mathbf{e}_{\Omega_1},
\end{aligned} \tag{7.136}$$

1444 The coupling matrix is then defined by

$$\mathbf{C} := \mathbf{B}_{\Gamma_{12}}^{\Omega_1} \mathbf{M}_{\partial,12}^{-1} \mathbf{B}_{\Gamma_{12}}^{\Omega_2 \top}. \tag{7.137}$$

1445 Plugging Eq. (7.136) into 7.134, 7.135, the final system with mixed causality is obtained

$$\begin{aligned} \begin{bmatrix} \mathbf{M}_{\Omega_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\Omega_2} \end{bmatrix} \begin{pmatrix} \dot{\mathbf{e}}_{\Omega_1} \\ \dot{\mathbf{e}}_{\Omega_2} \end{pmatrix} &= \begin{bmatrix} \mathbf{J}_{\Omega_1} & \pm \mathbf{C} \\ \mp \mathbf{C}^\top & \mathbf{J}_{\Omega_2} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{\Omega_1} \\ \mathbf{e}_{\Omega_2} \end{pmatrix} + \begin{bmatrix} \mathbf{B}_{\Gamma_1}^{\Omega_1} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{\Gamma_2}^{\Omega_2} \end{bmatrix} \begin{pmatrix} \mathbf{u}_{\partial,1} \\ \mathbf{u}_{\partial,2} \end{pmatrix}, \\ \begin{bmatrix} \mathbf{M}_{\partial,1} & \mathbf{0} \\ \mathbf{0} & \mathbf{M}_{\partial,2} \end{bmatrix} \begin{pmatrix} \mathbf{y}_{\partial,1} \\ \mathbf{y}_{\partial,2} \end{pmatrix} &= \begin{bmatrix} \mathbf{B}_{\Gamma_1}^{\Omega_1 \top} & \mathbf{0} \\ \mathbf{0} & \mathbf{B}_{\Gamma_2}^{\Omega_2 \top} \end{bmatrix} \begin{pmatrix} \mathbf{e}_{\Omega_1} \\ \mathbf{e}_{\Omega_2} \end{pmatrix}. \end{aligned} \quad (7.138)$$

1446 The total Hamiltonian is the sum

$$H_d = H_{d,1} + H_{d,2} = \frac{1}{2} \mathbf{e}_{\Omega_1}^\top \mathbf{M}_{\Omega_1} \mathbf{e}_{\Omega_1} + \frac{1}{2} \mathbf{e}_{\Omega_2}^\top \mathbf{M}_{\Omega_2} \mathbf{e}_{\Omega_2}. \quad (7.139)$$

1447 So, the power rate is

$$\begin{aligned} \dot{H}_d &= \mathbf{e}_{\Omega_1}^\top \mathbf{M}_{\Omega_1} \dot{\mathbf{e}}_{\Omega_1} + \mathbf{e}_{\Omega_2}^\top \mathbf{M}_{\Omega_2} \dot{\mathbf{e}}_{\Omega_2}, \\ &= \mathbf{e}_{\Omega_1}^\top \mathbf{J}_{\Omega_1} \mathbf{e}_{\Omega_1} + \mathbf{e}_{\Omega_2}^\top \mathbf{J}_{\Omega_2} \mathbf{e}_{\Omega_2} \pm \mathbf{e}_{\Omega_1}^\top \mathbf{C} \mathbf{e}_{\Omega_2} \mp \mathbf{e}_{\Omega_2}^\top \mathbf{C}^\top \mathbf{e}_{\Omega_1} + \mathbf{e}_{\Omega_1}^\top \mathbf{B}_{\Gamma_1}^{\Omega_1} \mathbf{u}_{\partial,1} + \mathbf{e}_{\Omega_2}^\top \mathbf{B}_{\Gamma_2}^{\Omega_2} \mathbf{u}_{\partial,2}, \\ &= \mathbf{y}_{\partial,1}^\top \mathbf{M}_{\partial,1} \mathbf{u}_{\partial,1} + \mathbf{y}_{\partial,2}^\top \mathbf{M}_{\partial,2} \mathbf{u}_{\partial,2}, \\ &= \hat{\mathbf{y}}_{\partial,1}^\top \mathbf{u}_{\partial,1} + \hat{\mathbf{y}}_{\partial,2}^\top \mathbf{u}_{\partial,2}, \quad \text{where} \quad \hat{\mathbf{y}}_{\partial,1} := \mathbf{M}_{\partial,1} \mathbf{y}_{\partial,1}, \quad \hat{\mathbf{y}}_{\partial,2} := \mathbf{M}_{\partial,2} \mathbf{y}_{\partial,2}. \end{aligned} \quad (7.140)$$

1448 Again this results mimics its corresponding infinite-dimensional (7.106).

1449

1450 This technique allows obtaining a system with the correct causality, but has some draw-
 1451 backs. Suitable finite elements are required for both kind of discretization detailed in Sec.
 1452 7.1.1, but the two are not always available (see Remark 9). A rigorous numerical convergence
 1453 analysis of this technique appears rather involved. Some cases of mixed conditions, in par-
 1454 ticular conditions on single components of vectors, cannot be handled by this technique. For
 1455 example, the simply supported condition in beams and plates imposes zero normal compo-
 1456 nent of the traction at the boundary. Furthermore two different meshes are required and the
 1457 interconnection has to manipulate carefully the degrees of freedom. This makes the imple-
 1458 mentation heavier than the Lagrange multiplier solution §7.2.1.

1459 7.3 Conclusion

1460 In this chapter a universal discretization method for multi-dimensional pHs has been detailed.
 1461 The underlying Assumptions 2, 3 are indeed those that characterize the well-posedness of
 1462 multi-dimensional pHs [Skr19]. For the time being, it has being shown that this technique
 1463 is capable of constructing a finite-dimensional pHs from an infinite-dimensional one. For
 1464 this reason, it is a structure-preserving method. The questions of numerical convergence and
 1465 choice of approximation basis (in this thesis the focus is on the finite element method but
 1466 spectral methods can be employed as well) are addressed in the next chapter, for the linear
 1467 case only.

Convergence numerical study

Aristotle maintained that women have fewer teeth than men; although he was twice married, it never occurred to him to verify this statement by examining his wives' mouths.

The Impact of Science on Society
Bertrand Russell



He application of the Partitioned Finite Element leads to a finite-dimensional systems

8.1 Plate problems using known mixed finite elements

In this section, the mixed finite element discretization of plate models in pH form is studied. These models have been recently presented in [?, ?], but without any convergence analysis. Here, available mixed finite elements for the wave dynamics and elastodynamics are adapted to the Mindlin plate problem. Error bounds are conjectured. For the Kirchhoff plate, the differential operator is of second order. Hence, more regular elements are required. The Hellan-Herrmann-Jhonson scheme is used ([?, ?]). It is conjectured that the convergence results valid for the static problem carry over to the dynamical case. Numerical simulations are implemented to confirm our conjectures.

The paper is organized as follows. In Section 8.2, plate models as port-Hamiltonian systems are briefly recalled. In Sec. 8.3, the weak formulation and corresponding finite element combinations are illustrated. The discretization relies on existing finite elements, hence the numerical implementation requires little effort. In Sec. 8.4, the numerical results, which confirm the expected behavior, are presented. The implementation is performed using the Firedrake python library ([RHM⁺17]).

8.2 Plate models in port-Hamiltonian form

In this section the models under consideration are recalled. More details can be found in [?] for the Mindlin plate and in [?] for the Kirchhoff plate.

1492 **8.2.1 Notations**

The space of all, symmetric and skew-symmetric $d \times d$ matrices are denoted by $\mathbb{M}, \mathbb{S}, \mathbb{K}$ respectively. The space of \mathbb{R}^d vectors is denoted by \mathbb{V} . $\Omega \subset \mathbb{R}^d$ is an open connected set. The geometric dimension of interest in this paper is $d = 2$. For a scalar field $u : \Omega \rightarrow \mathbb{R}$ the gradient is defined as

$$\text{grad}(u) = \nabla u := \left(\partial_{x_1} u \dots \partial_{x_d} u \right)^\top.$$

For a vector field $\mathbf{u} : \Omega \rightarrow \mathbb{V}$, with components u_j , the gradient (Jacobian) is defined as

$$\text{grad}(\mathbf{u})_{ij} := (\nabla \mathbf{u})_{ij} = \partial_{x_j} u_i.$$

The symmetric part of the gradient operator Grad (i. e. the deformation tensor in continuum mechanics) is thus given by

$$\text{Grad}(\mathbf{u}) := \frac{1}{2} \left(\nabla \mathbf{u} + \nabla^\top \mathbf{u} \right).$$

The Hessian operator of u is then computed as follows

$$\text{Hess}(u) = \nabla^2 u = \text{Grad}(\text{grad}(u)),$$

For a tensor field $\mathbf{U} : \Omega \rightarrow \mathbb{M}$, with components u_{ij} , the divergence is a vector, defined column-wise as

$$\text{Div}(\mathbf{U}) = \nabla \cdot \mathbf{U} := \left(\sum_{i=1}^d \partial_{x_i} u_{ij} \right)_{j=1, \dots, d}.$$

The double divergence of a tensor field \mathbf{U} is then a scalar field defined as

$$\text{div}(\text{Div}(\mathbf{U})) := \sum_{i,j=1}^d \partial_{x_i} \partial_{x_j} u_{ij}.$$

The L^2 inner products of scalar, vector and matrix fields are defined as

$$\begin{aligned} (u, v) &= \int_{\Omega} u v \, d\Omega, \quad u, v : \Omega \rightarrow \mathbb{R}, \\ (\mathbf{u}, \mathbf{v}) &= \int_{\Omega} \mathbf{u} \cdot \mathbf{v} \, d\Omega, \quad \mathbf{u}, \mathbf{v} : \Omega \rightarrow \mathbb{V}, \\ (\mathbf{U}, \mathbf{V}) &= \int_{\Omega} \mathbf{U} : \mathbf{V} \, d\Omega, \quad \mathbf{U}, \mathbf{V} : \Omega \rightarrow \mathbb{M}, \end{aligned}$$

where $\mathbf{u} \cdot \mathbf{v} := \sum_i u_i v_i$ is the scalar product in \mathbb{V} and $\mathbf{U} : \mathbf{V} := \sum_{i,j} u_{ij} v_{ij}$ is the tensor contraction. The standard notation $H^m(\Omega)$ denotes the Sobolev space of square integrable functions with m^{th} derivative in L^2 and norm $\|\cdot\|_m$. In particular, $H_0^1(\Omega)$ is the space of weakly derivable functions with vanishing trace. For $\mathbb{X} \subseteq \mathbb{M}$, let

$$\begin{aligned} H(\text{div}, \Omega) &= \{\mathbf{u} \in L^2(\Omega, \mathbb{V}) \mid \text{div}(\mathbf{u}) \in L^2(\Omega)\}, \\ H(\text{Div}, \Omega; \mathbb{X}) &= \{\mathbf{U} \in L^2(\Omega, \mathbb{X}) \mid \text{Div}(\mathbf{U}) \in L^2(\Omega; \mathbb{V})\}, \end{aligned}$$

which are Hilbert spaces with the norm $\|\mathbf{u}\|_{\text{div}}^2 = \|\mathbf{u}\|^2 + \|\text{div}(\mathbf{u})\|^2$, $\|\mathbf{U}\|_{\text{Div}}^2 = \|\mathbf{U}\|^2 + \|\text{Div}(\mathbf{U})\|^2$. The following abbreviations will be used

$$\begin{aligned} M &= H(\text{Div}, \Omega; \mathbb{M}), & D &= H(\text{div}, \Omega), & V &= L^2(\Omega; \mathbb{V}), \\ S &= H(\text{Div}, \Omega; \mathbb{S}), & L &= L^2(\Omega), & K &= L^2(\Omega; \mathbb{K}). \end{aligned}$$

Let \mathcal{X} be a Hilbert space, and t_f a positive real number. We denote by $L^\infty([0, t_f]; \mathcal{X})$ or $L^\infty(\mathcal{X})$ the space of functions $f : [0, t_f] \rightarrow \mathcal{X}$ for which the time-space norm $\|\cdot\|_{L^\infty([0, t_f]; \mathcal{X})}$ satisfies

$$\|f\|_{L^\infty([0, t_f]; \mathcal{X})} = \text{ess sup}_{t \in [0, t_f]} \|f\|_{\mathcal{X}} < \infty.$$

8.2.2 Mindlin-Reissner plate

The Mindlin model is a generalization to the 2D case of the Timoshenko beam model and is expressed by a system of two coupled PDEs ([TWK59])

$$\begin{cases} \rho b \frac{\partial^2 w}{\partial t^2} &= \text{div}(\mathbf{q}) + f, & (\mathbf{x}, t) \in \Omega \times [0, t_f], \\ \frac{\rho b^3}{12} \frac{\partial^2 \boldsymbol{\theta}}{\partial t^2} &= \mathbf{q} + \text{Div}(\mathbf{M}) + \boldsymbol{\tau}, \end{cases} \quad (8.1)$$

where ρ is the mass density, b the plate thickness, w the vertical displacement, $\boldsymbol{\theta} = (\theta_x, \theta_y)^\top$ collects the deflection of the cross section along axes x and y respectively. The fields $f, \boldsymbol{\tau}$ represent distributed forces and torques. Variables \mathbf{M}, \mathbf{q} represent the momenta tensor and the shear stress. Hooke's law relates those to the curvature tensor and shear deformation vector

$$\begin{aligned} \mathbf{M} &:= \mathcal{D}\mathbf{K} \in \mathbb{S}, & \mathbf{K} &:= \text{Grad}(\boldsymbol{\theta}) \in \mathbb{S}, \\ \mathbf{q} &:= \mathcal{C}\boldsymbol{\gamma}, & \boldsymbol{\gamma} &:= \text{grad}(w) - \boldsymbol{\theta},. \end{aligned}$$

Tensors \mathcal{D}, \mathcal{C} are symmetric positive

$$\mathcal{D}(\cdot) = \frac{E_Y b^3}{12(1 - \nu^2)} [(1 - \nu)(\cdot) + \nu \text{Tr}(\cdot)], \quad \mathcal{C}(\cdot) = \frac{E b k}{2(1 + \nu)} (\cdot), \quad (8.2)$$

where E_Y is the Young modulus, ν is the Poisson modulus, k is the shear correction factor. The kinetic and potential energies E_c, E_p read

$$\begin{aligned} E_c &= \frac{1}{2} \int_{\Omega} \left\{ \rho b \left(\frac{\partial w}{\partial t} \right)^2 + \frac{\rho b^3}{12} \frac{\partial \boldsymbol{\theta}}{\partial t} \cdot \frac{\partial \boldsymbol{\theta}}{\partial t} \right\} d\Omega, \\ E_p &= \frac{1}{2} \int_{\Omega} \{ \mathbf{M} : \mathbf{K} + \mathbf{q} \cdot \boldsymbol{\gamma} \} d\Omega. \end{aligned} \quad (8.3)$$

The Hamiltonian is easily written as $H = E_c + E_p$. To get a port-Hamiltonian formulation, suitable energy variables must be selected. The appropriate set is the following:

$$\begin{aligned} \alpha_w &= \rho b \frac{\partial w}{\partial t}, & \alpha_\theta &= \frac{\rho b^3}{12} \frac{\partial \theta}{\partial t}, \\ \mathbf{A}_\kappa &= \mathbf{K}, & \alpha_\gamma &= \gamma. \end{aligned} \quad (8.4)$$

The co-energy variables are found by computing the variational derivatives of the Hamiltonian

$$\begin{aligned} e_w &:= \frac{\delta H}{\delta \alpha_w} = \frac{\partial w}{\partial t}, & e_\theta &:= \frac{\delta H}{\delta \alpha_\theta} = \frac{\partial \theta}{\partial t}, \\ \mathbf{E}_\kappa &:= \frac{\delta H}{\delta \mathbf{A}_\kappa} = \mathbf{M}, & e_\gamma &:= \frac{\delta H}{\delta \alpha_\gamma} = \mathbf{q}. \end{aligned} \quad (8.5)$$

Energy and co-energy variables are related by a positive symmetric operator $\alpha = \mathcal{Q}e$

$$\mathcal{Q} = \text{diag}[(\rho b)^{-1}, (\rho b^3/12)^{-1}, \mathcal{D}, \mathcal{C}]. \quad (8.6)$$

The port-Hamiltonian system is expressed as follows

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \alpha_\theta \\ \mathbf{A}_\kappa \\ \alpha_\gamma \end{pmatrix} = \underbrace{\begin{bmatrix} 0 & 0 & 0 & \text{div} \\ 0 & 0 & \text{Div} & \mathbf{I}_{2 \times 2} \\ 0 & \text{Grad} & 0 & 0 \\ \text{grad} & -\mathbf{I}_{2 \times 2} & 0 & 0 \end{bmatrix}}_{\mathcal{J}} \begin{pmatrix} e_w \\ e_\theta \\ \mathbf{E}_\kappa \\ e_\gamma \end{pmatrix} + \begin{pmatrix} f \\ \boldsymbol{\tau} \\ 0 \\ 0 \end{pmatrix}. \quad (8.7)$$

Remark 12

The force and torque $f, \boldsymbol{\tau}$ define a distributed control \mathbf{u}_d . Together with the collocated distributed output $\mathbf{y}_d = [e_w, e_\theta]^\top$, this system defines a Dirac structure. By computing the power balance, it would be possible to add boundary variables $\mathbf{u}_\partial, \mathbf{y}_\partial$, and, consequently, to obtain a Stokes-Dirac structure. However, in this paper we focus on clamped boundary condition, i.e.

$$e_w|_{\partial\Omega} = 0, \quad e_\theta|_{\partial\Omega} = 0 \implies \mathbf{u}_\partial = [e_w|_{\partial\Omega}, e_\theta|_{\partial\Omega}]^\top \equiv 0.$$

More general boundary conditions may be treated as well.

8.2.3 Kirchhoff plate

The Kirchhoff plate model is a generalization to the 2D case of the Euler-Bernoulli beam model. The classical equations for this model are ([TWK59])

$$\rho b \frac{\partial^2 w}{\partial t^2} = -\text{div}(\text{Div}(\mathbf{M})) + f, \quad (\mathbf{x}, t) \in \Omega \times [0, t_f]. \quad (8.8)$$

As in the Mindlin model, the bending moment tensor and the curvature are related $\mathbf{M} = \mathcal{D}\mathbf{K} \in \mathbb{S}$ (with \mathcal{D} defined in (8.2)). Following the Kirchhoff assumption, the curvature tensor

is the Hessian of the vertical displacement

$$\mathbf{K} := \text{Grad}(\text{grad}(w)) \in \mathbb{S}.$$

1516 The kinetic and potential energy E_c, E_p read

$$E_c = \frac{1}{2} \int_{\Omega} \rho b \left(\frac{\partial w}{\partial t} \right)^2 d\Omega, \quad E_p = \frac{1}{2} \int_{\Omega} \mathbf{M} : \mathbf{K} d\Omega. \quad (8.9)$$

1517 The Hamiltonian is then given by $H = E_c + E_p$. Selecting as energy variables

$$\alpha_w = \rho b \frac{\partial w}{\partial t}, \quad \mathbf{A}_{\kappa} = \mathbf{K}, \quad (8.10)$$

1518 the co-energy variables are found by computing the variational derivatives of the Hamiltonian

$$e_w := \frac{\delta H}{\delta \alpha_w} = \frac{\partial w}{\partial t}, \quad \mathbf{E}_{\kappa} := \frac{\delta H}{\delta \mathbf{A}_{\kappa}} = \mathbf{M}. \quad (8.11)$$

1519 The coercive operator linking energy and co-energy variables reads

$$\mathcal{Q} = \text{diag}[(\rho b)^{-1}, \mathcal{D}]. \quad (8.12)$$

1520 The port-Hamiltonian system is expressed as follows

$$\frac{\partial}{\partial t} \begin{pmatrix} \alpha_w \\ \mathbf{A}_{\kappa} \end{pmatrix} = \underbrace{\begin{bmatrix} 0 & -\text{div} \circ \text{Div} \\ \text{Grad} \circ \text{grad} & 0 \end{bmatrix}}_{\mathcal{J}} \begin{pmatrix} e_w \\ \mathbf{E}_{\kappa} \end{pmatrix} + \begin{pmatrix} f \\ 0 \end{pmatrix}. \quad (8.13)$$

1521 Following Remark 12 this system would define a Stokes-Dirac if appropriate boundary vari-
1522 ables were added. However, in this paper simply supported boundary conditions are consid-
1523 ered, i.e.

$$e_w|_{\partial\Omega} = 0, \quad m_{nn}|_{\partial\Omega} := \mathbf{n}^{\top} \mathbf{E}_{\kappa} \mathbf{n}|_{\partial\Omega} = 0,$$

1524 hence no boundary control is present. Differently from the Mindlin plate case, generic bound-
1525 ary conditions demand an accurate analysis, see for instance [?, ?].

1526 8.3 Available mixed finite elements

1527 In this section suitable semi-discretized models are derived. For the Mindlin model, two
1528 different formulation are presented: the first one enforces the symmetry of the momenta
1529 tensor strongly (§8.3.1), the second weakly (§8.3.2). For the Kirchhoff plate, the formulation
1530 is based on the the non-conforming Hellan-Herrmann-Johnson method (HHJ) (§8.3.3).

1531 Remark 13

1532 System (8.7), (8.13) can be expressed using either the energy or the co-energy variables. The

most adapted formulation to the existing mixed finite element literature is the co-energy one, which reads $\mathcal{Q}^{-1}\partial_t \mathbf{e} = \mathcal{J}\mathbf{e}$.

8.3.1 Mindlin plate with strongly imposed symmetry

The weak formulation with strongly imposed symmetry seeks $\{e_w, \mathbf{e}_\theta, \mathbf{E}_\kappa, \mathbf{e}_\gamma\} \in L \times V \times S \times D$ so that

$$\begin{aligned} (v_w, \rho b \dot{e}_w) &= (v_w, \operatorname{div} \mathbf{e}_\gamma) + (v_w, f), & v_w &\in L, \\ (\mathbf{v}_\theta, \rho b^3/12 \dot{\mathbf{e}}_\theta) &= (\mathbf{v}_\theta, \operatorname{Div} \mathbf{E}_\kappa + \mathbf{e}_\gamma) + (\mathbf{v}_\theta, \boldsymbol{\tau}), & \mathbf{v}_\theta &\in V, \\ (\mathbf{V}_\kappa, \mathcal{D}^{-1} \dot{\mathbf{E}}_\kappa) &= -(\operatorname{Div} \mathbf{V}_\kappa, \mathbf{e}_\theta), & \mathbf{V}_\kappa &\in S, \\ (\mathbf{v}_\gamma, \mathcal{C}^{-1} \dot{\mathbf{e}}_\gamma) &= -(\operatorname{div} \mathbf{v}_\gamma, e_w) + (\mathbf{v}_\gamma, \mathbf{e}_\theta), & \mathbf{v}_\gamma &\in D. \end{aligned} \tag{8.14}$$

This formulation is obtained by multiplying each equation by a test function belonging to the same space as the corresponding unknown, and integrating over the domain. The final system is obtained by integrating by parts the last two lines of (8.7) and considering clamped boundary conditions. Obtaining stable finite elements that embed the symmetry of the stress tensor for the elastodynamics problem has proven to be a difficult task. The easiest implementation is the one presented in [?, ?]. The main disadvantage is that this scheme requires the domain to be given by a union of rectangles, as the mesh elements have to be square. However, this allows constructing a simple element for the momenta tensor. The polynomial spaces for the discretization are

$$N_k = \{p(x, y) \mid p(x, y) = \sum_{i \leq k, j \leq k} a_{ij} x^i y^j\}.$$

Given a regular mesh \mathcal{R}_h with square elements Q the following spaces are introduced as discretization spaces

$$\begin{aligned} L_h^{\text{BJT}} &= \{w_h \in L \mid \forall Q, w_h|_Q \in N_{k-1}\}, \\ V_h^{\text{BJT}} &= \{\boldsymbol{\theta}_h \in V \mid \forall Q, \boldsymbol{\theta}_h|_Q \in (N_{k-1})^2\}, \\ S_h^{\text{BJT}} &= \{m_{12} \in H^1(\Omega) \mid \forall Q, m_{12}|_Q \in N_k\} \\ &\quad \cup \{(m_{11}, m_{22}) \in D \mid \forall Q, (m_{11}, m_{22})|_Q \in N_k\}, \\ D_h^{\text{BJT}} &= \{\mathbf{q}_h \in D \mid \forall Q, \mathbf{q}_h|_Q \in N_k\}, \end{aligned} \tag{8.15}$$

where BTJ stands for the initials of the authors in [?, ?]. Combining the results of both papers, the following error estimates are conjectured:

Conjecture 4

Assuming a smooth solution to problem (8.14), the following error estimates hold

$$\begin{aligned} \|e_w - e_w^h\|_{L^\infty(L^2)} &\lesssim h^k, & \|\mathbf{E}_\kappa - \mathbf{E}_\kappa^h\|_{L^\infty(L^2)} &\lesssim h^k, \\ \|\mathbf{e}_\theta - \mathbf{e}_\theta^h\|_{L^\infty(L^2)} &\lesssim h^k, & \|\mathbf{e}_\gamma - \mathbf{e}_\gamma^h\|_{L^\infty(L^2)} &\lesssim h^k, \end{aligned} \tag{8.16}$$

where the notation $a \lesssim b$ means $a \leq Cb$. The constant C depends only on the true solution

1554 and on the final time.

1555 8.3.2 Mindlin plate with weakly imposed symmetry

1556 Formulation (8.14) has to be modified to impose the symmetry of the momenta tensor weakly.
 1557 Taking the weak form of the third equation in (8.7), we get

$$(\mathbf{V}_\kappa, \mathcal{D}^{-1} \dot{\mathbf{E}}_\kappa) = (\mathbf{V}_\kappa, \text{Grad } \mathbf{e}_\theta).$$

1558 The symmetric gradient can be rewritten as

$$\text{Grad } \boldsymbol{\theta} = \text{grad } \boldsymbol{\theta} - \text{skw}(\text{grad } \boldsymbol{\theta}),$$

where $\text{skw}(\mathbf{A}) = (\mathbf{A} - \mathbf{A}^\top)/2$ is the skew-symmetric part of matrix \mathbf{A} . Introducing the new variable $\mathbf{E}_r = \text{skw}(\text{grad } \boldsymbol{\theta})$, then $\{\mathbf{e}_\theta, \mathbf{E}_\kappa, \mathbf{E}_r\} \in V \times M \times K$ satisfy (remind that $\mathbf{e}_\theta = \partial_t \boldsymbol{\theta}$)

$$\begin{aligned} (\mathbf{V}_\kappa, \mathcal{D}^{-1} \dot{\mathbf{E}}_\kappa) &= (\mathbf{V}_\kappa, \text{grad } \mathbf{e}_\theta) - (\mathbf{V}_\kappa, \dot{\mathbf{E}}_r), \\ &= -(\text{Div } \mathbf{V}_\kappa, \mathbf{e}_\theta) - (\mathbf{V}_\kappa, \dot{\mathbf{E}}_r). \end{aligned}$$

1559 The momenta tensor is weakly symmetric if $(\mathbf{V}_r, \mathbf{E}_\kappa) = 0$. The weak formulation then consists
 1560 in finding
 1561 $\{e_w, \mathbf{e}_\theta, \mathbf{E}_\kappa, \mathbf{e}_\gamma, \mathbf{E}_r\}$ in $L \times V \times M \times D \times K$ so that

$$\begin{aligned} (v_w, \rho b \dot{e}_w) &= (v_w, \text{div } \mathbf{e}_\gamma) + (v_w, f), & v_w &\in L, \\ (\mathbf{v}_\theta, \rho b^3/12 \dot{\mathbf{e}}_\theta) &= (\mathbf{v}_\theta, \text{Div } \mathbf{E}_\kappa + \mathbf{e}_\gamma) + (\mathbf{v}_\theta, \boldsymbol{\tau}), & \mathbf{v}_\theta &\in V, \\ (\mathbf{V}_\kappa, \mathcal{D}^{-1} \dot{\mathbf{E}}_\kappa) &= -(\text{Div } \mathbf{V}_\kappa, \mathbf{e}_\theta) - (\mathbf{V}_\kappa, \dot{\mathbf{E}}_r), & \mathbf{V}_\kappa &\in S, \\ (\mathbf{v}_\gamma, \mathcal{C}^{-1} \dot{\mathbf{e}}_\gamma) &= -(\text{div } \mathbf{v}_\gamma, e_w) + (\mathbf{v}_\gamma, \mathbf{e}_\theta), & \mathbf{v}_\gamma &\in D, \\ (\mathbf{V}_r, \dot{\mathbf{E}}_\kappa) &= 0 & \mathbf{V}_r &\in K, \end{aligned} \tag{8.17}$$

1562 Consider a regular triangulation \mathcal{T}_h with elements T . The space of polynomials of order k on
 1563 a mesh cell is denoted by P_k . The following spaces are used as discretization spaces

$$\begin{aligned} L_h^{\text{AFW}} &= \{w_h \in L \mid \forall T, w_h|_T \in P_{k-1}\}, \\ V_h^{\text{AFW}} &= \{\boldsymbol{\theta}_h \in V \mid \forall T, \boldsymbol{\theta}_h|_T \in (P_{k-1})^2\}, \\ S_h^{\text{AFW}} &= \{(m_{11}, m_{12}) \in D \mid \forall T, (m_{11}, m_{12})|_T \in BDM_{[k]}\} \\ &\quad \cup \{(m_{21}, m_{22}) \in D \mid \forall T, (m_{21}, m_{22})|_T \in BDM_{[k]}\}, \\ D_h^{\text{AFW}} &= \{\mathbf{q}_h \in D \mid \forall T, \mathbf{q}_h|_T \in RT_{[k-1]}\}, \\ K_h^{\text{AFW}} &= \{\mathbf{R}_h \in K \mid \forall T, \mathbf{R}_h|_T \in P_{k-1}\}, \end{aligned} \tag{8.18}$$

1564 where BDM are the Brezzi-Douglas-Marini elements and RT the Raviart-Thomas elements.
 1565 The acronym AFW stands for Arnold-Falk-Winther. A convergence analysis for the general
 1566 elastodynamics problem with weak symmetry in the $L^\infty(L^2)$ norm is detailed [?]. A conver-
 1567 gence study for the wave equation with mixed finite elements in the $L^\infty(L^2)$ is presented in

[?]. Combining the results of the two, the following error estimates are conjectured:

Conjecture 5

Assuming a smooth solution to problem (8.14), the following error estimates hold

$$\begin{aligned} \|e_w - e_w^h\|_{L^\infty(L^2)} &\lesssim h^k, & \|\mathbf{E}_\kappa - \mathbf{E}_\kappa^h\|_{L^\infty(L^2)} &\lesssim h^k, \\ \|e_\theta - e_\theta^h\|_{L^\infty(L^2)} &\lesssim h^k, & \|e_\gamma - e_\gamma^h\|_{L^\infty(L^2)} &\lesssim h^k, \\ \|\mathbf{E}_r - \mathbf{E}_r^h\|_{L^\infty(L^2)} &\lesssim h^k. \end{aligned} \quad (8.19)$$

8.3.3 The HHJ scheme for the Kirchhoff plate

For the Kirchhoff plate, the HHJ scheme can be used to obtain a structure-preserving discretization. The discussion follows [?]. Given the non conforming nature of this scheme, it is necessary to first introduce the discrete functional spaces and state the problem directly in discrete form. The vertical displacement is approximated using continuous Lagrange polynomials, while the momenta tensor is discretized using the HHJ element

$$\begin{aligned} W_h &= \{w_h \in H_0^1(\Omega) \mid \forall T, w_h|_T \in P_k\}, \\ U_h &= \{\mathbf{M}_h \in L^2(\Omega, \mathbb{S}) \mid \forall T, \mathbf{M}_h|_T \in P_{k-1}(\mathbb{S}), \\ &\quad \mathbf{M}_h \text{ is normal-normal continuous across elements}\}. \end{aligned} \quad (8.20)$$

The normal to normal continuity means that if two triangles T_1, T_2 share a common edge E then $\mathbf{n}^\top(\mathbf{M}_h|_{T_1})\mathbf{n} = \mathbf{n}^\top(\mathbf{M}_h|_{T_2})\mathbf{n}$ on E . Taking system (8.13) and multiplying the first equation by $v_w \in W_h$ and integrating over a triangle

$$\begin{aligned} &-(v_w, \operatorname{div} \operatorname{Div} \mathbf{E}_\kappa)_T = (\nabla v_w, \operatorname{Div} \mathbf{E}_\kappa)_T =, \\ &-(\nabla^2 v_w, \mathbf{E}_\kappa)_T + (\partial_n v_w, \mathbf{n}^\top \mathbf{E}_\kappa \mathbf{n})_{\partial T} + (\partial_s v_w, \mathbf{s}^\top \mathbf{E}_\kappa \mathbf{n})_{\partial T}. \end{aligned}$$

A double integration by parts is applied to get the final equation. Summing up over all triangles provides for the penultimate term

$$\sum_{T \in \mathcal{T}_h} (\partial_n v_w, \mathbf{n}^\top \mathbf{E}_\kappa \mathbf{n})_{\partial T} = \sum_{E \in \mathcal{E}_h} ([\partial_n v_w], m_{nn})_E,$$

where \mathcal{E}_h is the set of all edges belonging to the mesh and $[a] = a|_{T_1} + a|_{T_2}$ denotes the jump of a function across shared edges. For a boundary edge it is simply the value of the function. For the final term, it holds $(\partial_s v_w, \mathbf{s}^\top \mathbf{E}_\kappa \mathbf{n})_{\partial T} = 0$, since v_w is continuous across the edge boundaries and the normal switches sign. We are now in a position to state the final weak form. Given the definition

$$b_h(v_w, \mathbf{E}_\kappa) := - \sum_{T \in \mathcal{T}_h} (\nabla^2 v_w, \mathbf{E}_\kappa)_T + \sum_{E \in \mathcal{E}_h} ([\partial_n v_w], m_{nn})_E,$$

1582 find $(e_w, \mathbf{E}_\kappa) \in W_h \times U_h$ such that

$$\begin{aligned} (v_w, \rho b \dot{e}_w) &= +b_h(v_w, \mathbf{E}_\kappa) + (v_w, f), & v_w &\in W_h, \\ (\mathbf{V}_\kappa, \mathcal{D}^{-1} \dot{\mathbf{E}}_\kappa) &= -b_h(e_w, \mathbf{V}_\kappa), & \mathbf{V}_\kappa &\in U_h. \end{aligned} \quad (8.21)$$

1583 For the associated static problem, under the hypothesis of smooth solutions, optimal
1584 convergence of order $O(k)$ for $w \in H^1$ and $\mathbf{M} \in L^2$ has been established. So, it is natural to
1585 conjecture the following result for the dynamic problem:

1586 Conjecture 6

1587 *Assuming a smooth solution for problem (8.21), the following error estimates hold*

$$\|e_w - e_w^h\|_{L^\infty(H^1)} \lesssim h^k, \quad \|\mathbf{E}_\kappa - \mathbf{E}_\kappa^h\|_{L^\infty(L^2)} \lesssim h^k. \quad (8.22)$$

1588 8.4 Numerical experiments

1589 In this section numerical test cases are used to verify the conjectured orders of convergence
1590 for the two problems. Upon discretization, system (8.14), (8.17), (8.21) assumes the form

$$M \dot{\mathbf{e}} = J \mathbf{e}.$$

1591 Matrix J is skew-symmetric, matrix M is symmetric and positive definite for (8.14), (8.21)
1592 while it is symmetric but indefinite for (8.17), because of the multiplier that enforces the
1593 symmetry. The Firedrake library ([RHM⁺17]) is used to generate the matrices. To integrate
1594 the equations in time a Crank-Nicholson scheme has been used, for all simulations. The time
1595 step is set to $\Delta t = h/10$ to have a lower impact of the time discretization error with respect
1596 to the spatial error. The final time is set to one $t_f = 1[\text{s}]$ for all simulations. To compute the
1597 $L^\infty(\mathcal{X})$ space-time dependent norm the discrete norm $L_{\Delta t}^\infty(\mathcal{X})$ is used

$$\|\cdot\|_{L^\infty(\mathcal{X})} \approx \|\cdot\|_{L_{\Delta t}^\infty(\mathcal{X})} = \max_{t \in t_i} \|\cdot\|_{\mathcal{X}},$$

1598 where t_i are the discrete simulation instants.

1599 8.4.1 Numerical test for the Mindlin plate

Constructing an analytical solution for a vibrating Mindlin plate is far from trivial. Therefore, the solution for the static case presented in [?] is exploited.

Step 1 Consider a distributed static force given by

$$\begin{aligned} f_s(x, y) = & \frac{E_Y}{12(1-\nu^2)} \{12y(y-1)(5x^2-5x+1) \\ & \times [2y^2(y-1)2 + x(x-1)(5y^2-5y+1)] + 12x(x-1) \\ & \times (5y^2-5y+1)[2x^2(x-1)2 + y(y-1)(5x^2-5x+1)]\}. \end{aligned}$$

The static displacement and rotation are given by

$$\begin{aligned} w_s(x, y) = & \frac{1}{3}x^3(x-1)^3y^3(y-1)^3 \\ & - \frac{2b^2}{5(1-\nu)}[y^3(y-1)^3x(x-1)(5x^2-5x+1). \\ \theta_s(x, y) = & \begin{pmatrix} y^3(y-1)^3 x^2(x-1)^2(2x-1) \\ x^3(x-1)^3 y^2(y-1)^2(2y-1) \end{pmatrix} \end{aligned}$$

1600 The static solution solves the following problem defined on the square domain $\Omega = (0, 1) \times$
1601 $(0, 1)$:

$$\begin{aligned} 0 = \operatorname{div} \mathbf{q}_s + f_s, \quad \mathcal{D}^{-1} \mathbf{M}_s &= \operatorname{Grad} \boldsymbol{\theta}_s, \\ 0 = \operatorname{Div} \mathbf{M}_s + \mathbf{q}_s, \quad \mathcal{C}^{-1} \mathbf{q}_s &= \operatorname{grad} w_s - \boldsymbol{\theta}_s. \end{aligned} \quad (8.23)$$

1602 **Step 2** Given the linear nature of the system a solution for the dynamic problem is found
1603 by multiplying the static solution by a time dependent term. For simplicity a sinus function
1604 is chosen

$$w_d(x, y, t) = w_s(x, y) \sin(t), \quad \boldsymbol{\theta}_d(x, y, t) = \boldsymbol{\theta}_s(x, y) \sin(t).$$

1605 For the port-Hamiltonian system velocities are needed

$$e_w^{\text{ex}}(x, y, t) = w_s(x, y) \cos(t), \quad e_\theta^{\text{ex}}(x, y, t) = \boldsymbol{\theta}_s(x, y) \cos(t).$$

1606 The momenta and shear force are then defined by

$$\mathbf{M}_d = \mathbf{E}_\kappa^{\text{ex}} = \mathcal{D} \operatorname{Grad} \boldsymbol{\theta}_d, \quad \mathbf{q}_d = \mathbf{e}_\gamma^{\text{ex}} = \mathcal{C}(\operatorname{grad} w_d - \boldsymbol{\theta}_d)$$

Step 3 Appropriate forcing terms have to be introduced (i.e. $f, \boldsymbol{\tau}$ in (8.1)). The force and torque in the dynamical case become

$$f_d = f_s \sin(t) + \rho b \partial_{tt} w_d, \quad \boldsymbol{\tau}_d = \frac{\rho b^3}{12} \partial_{tt} \boldsymbol{\theta}_d.$$

1607 Variables $(e_w^{\text{ex}}, e_\theta^{\text{ex}}, \mathbf{E}_\kappa^{\text{ex}}, \mathbf{e}_\gamma^{\text{ex}})$ under excitations $(f_d, \boldsymbol{\tau}_d)$ solve problem (8.7). The solution being
1608 smooth, the conjectured error estimates should hold. The numerical values of the physical
1609 parameters are reported in Table 8.3.

Plate parameters				
E	ρ	ν	K_{sh}	h
1 [Pa]	1 [kg/m ³]	0.3	5/6	0.1 [m]

Table 8.1: Physical parameters for the Mindlin plate.

1610 8.4.1.1 Results for the strong symmetry formulation

1611 The weak form (8.14) and its corresponding finite elements (8.15) was implemented using
 1612 Firedrake extruded mesh functionality ([?]). A direct solver based on an LU preconditioner
 1613 is used. In Fig. 8.1 the errors for $(e_w, e_\theta, \mathbf{E}_\kappa, e_\gamma)$ are reported. As one can notice, the
 1614 conjectured error estimates (8.16) are respected for all variables.

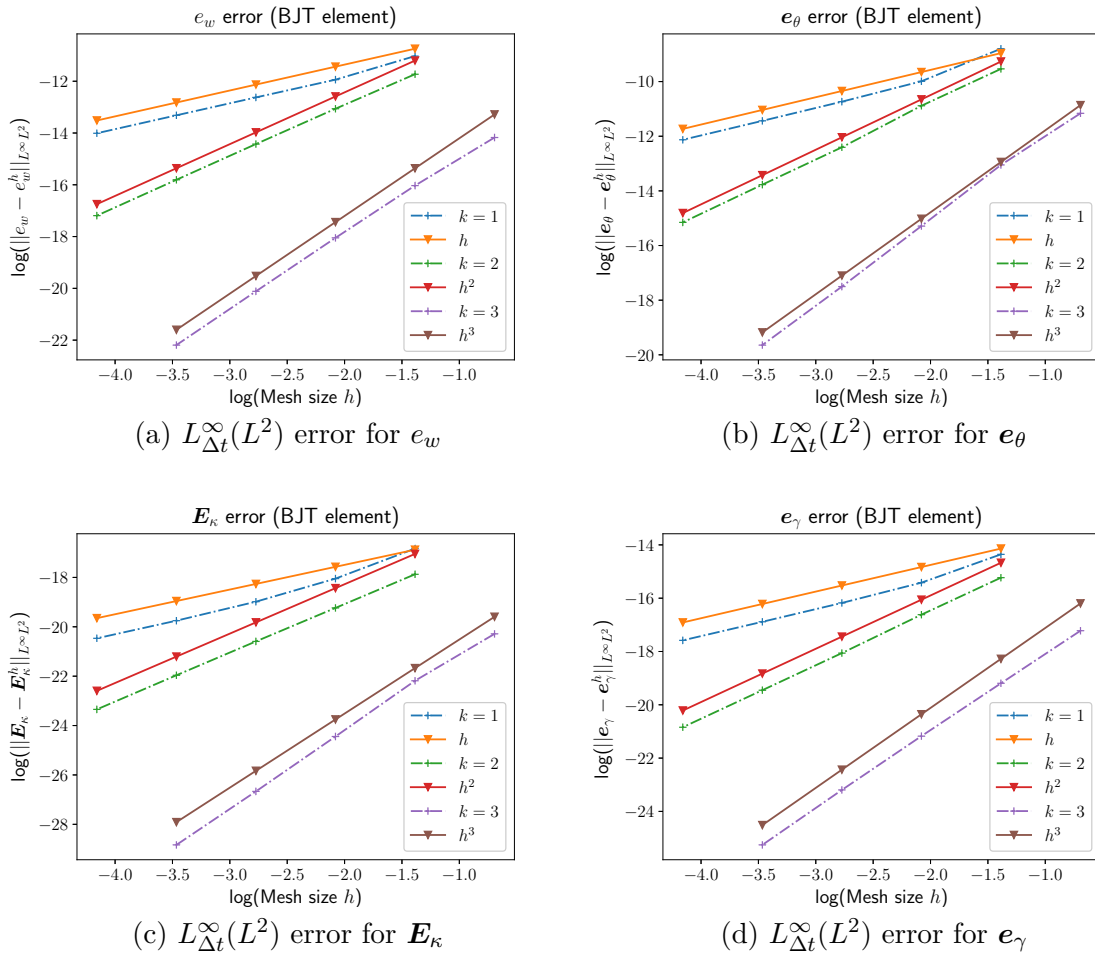


Figure 8.1: Error for the Mindlin plate using the BJT elements

8.4.1.2 Results for the weak symmetry formulation

Formulation (8.17) and its element (8.18) are considered here. A direct solver failed for high order cases (i.e. $k = 3$). For this reason a generalized minimal residual method is used with restart number of iterations equal to 100. In Fig. 8.2 the errors for variables $(e_w, e_\theta, \mathbf{E}_\kappa, e_\gamma)$ are reported. The errors for $(e_w, e_\theta, e_\gamma)$ respect the conjectured result (8.19). Variable \mathbf{E}_κ exhibit a superconvergence phenomenon for the case $k = 1$. In [?] no numerical study was carried out for the case $k = 1$. The BDM elements might be responsible for such superconvergence. The convergence order of $(\mathbf{E}_\kappa, e_\gamma)$ deteriorates for $k = 3$ for the finest mesh. This must be linked to errors due to the underlying large saddle-point problem. Indeed in [?] an hybridization method is used to transform the saddle-point problem into a symmetric positive definite one.

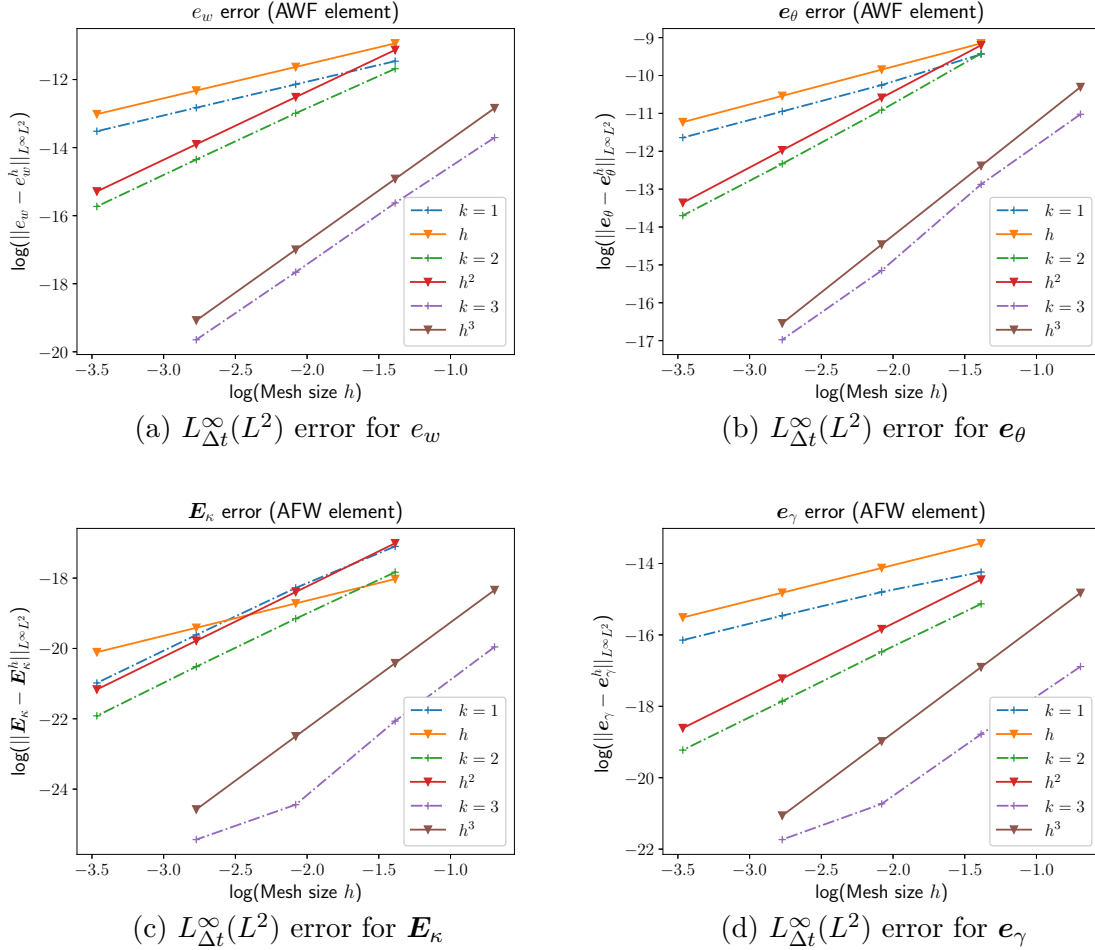


Figure 8.2: Error for the Mindlin plate using the AFW elements

8.4.2 Numerical test for the Kirchhoff plate

An analytical solution for the Kirchhoff plate is readily available. Consider the following solution of problem (8.8) under simply supported conditions on a square unitary domain

$$w^{\text{ex}}(x, y, t) = \sin(\pi x) \sin(\pi y) \sin(t), \quad (x, y) \in (0, 1) \times (0, 1).$$

The forcing term is given by

$$f = (4D\pi^4 - \rho b) \sin(\pi x) \sin(\pi y) \sin(t), \quad D = \frac{E_Y b^3}{12(1 - \nu^2)}.$$

The corresponding variables in the port-Hamiltonian frame work are

$$e_w^{\text{ex}} = \partial_t w^{\text{ex}}, \quad \mathbf{E}_\kappa^{\text{ex}} = \mathcal{D} \nabla^2 w^{\text{ex}}.$$

Variables $(e_w^{\text{ex}}, \mathbf{E}_\kappa^{\text{ex}})$ under excitation f solve problem (8.13). The physical parameters used in simulation are reported in Table 8.2. The weak form (8.21) and the finite elements (8.20) are considered. A direct solver with an LU preconditioner is used to compute the solution. Results are shown in Fig. 8.3. The conjectured error estimates are respected.

Plate parameters			
E	ρ	ν	h
136 [GPa]	5600 [kg/m ³]	0.3	0.001 [m]

Table 8.2: Physical parameters for the Kirchhoff plate.

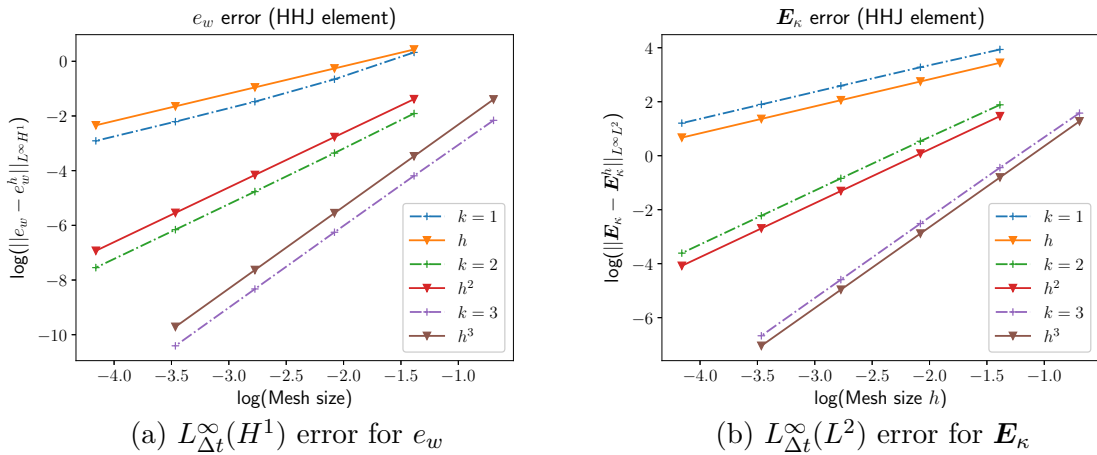


Figure 8.3: Error for the Kirchhoff plate using HHJ elements

8.5 Conclusion

In this paper, the link between mixed finite element method and pH plate models has been studied. It was shown that existing elements can be used to obtain structure-preserving discretization. A rigorous error analysis is still to be done but it should be easy to prove, given the available results. Since the pH framework provides a powerful description of boundary controlled systems, it is important that numerical methods be capable of handling generic boundary conditions. The methods discussed here possess this feature in the Mindlin plate case. For the Kirchhoff plate, a promising methodology is detailed in [?], but the dynamical case has not been considered yet. Future developments include the analysis and discretization of viscoelastic and thermoelastic problems in pH form.

8.6 Non-standard discretization of flexible structures

First of all we construct a family of finite elements capable of discretizing problem (??). Consider a regular triangulation \mathcal{T}_h with elements T . The space of polynomials of order k on a mesh cell is denoted by P_k . The following family of finite elements is conforming to the weak formulation (??)

$$\begin{aligned} H_h^1(\Omega) &= \{w_h \in H^1(\Omega) \mid \forall T, w_h|_T \in P_k\}, \\ H_h^{\text{Grad}}(\Omega, \mathbb{R}^2) &= \{\boldsymbol{\theta}_h \in H^{\text{Grad}}(\Omega, \mathbb{R}^2) \mid \forall T, \boldsymbol{\theta}_h|_T \in (P_k)^2\}, \\ L_h^2(\Omega, \mathbb{S}) &= \{\mathbf{M}_h \in L^2(\Omega, \mathbb{S}) \mid \forall T, \mathbf{M}_h|_T \in (P_{k-1})_{\text{sym}}^{2 \times 2}\}, \\ L_h^2(\Omega, \mathbb{R}^2) &= \{\mathbf{q}_h \in L^2(\Omega, \mathbb{R}^2) \mid \forall T, \mathbf{q}_h|_T \in (P_{k-1})^2\}, \end{aligned} \tag{8.24}$$

To approximate spaces $H_h^1(\Omega)$, $H_h^{\text{Grad}}(\Omega, \mathbb{R}^2)$ Lagrange polynomials of order k are selected. For spaces $L_h^2(\Omega, \mathbb{S})$, $L_h^2(\Omega, \mathbb{R}^2)$ Discontinuous Galerkin polynomials of order $k-1$ are employed. We use the acronym CGDG to denote this combination of elements

$$\text{CGDG} = \text{CG} \times \text{CG}(\mathbb{R}^2) \times \text{DG}(\mathbb{S}) \times \text{DG}(\mathbb{R}^2)$$

This selection of finite elements can be seen as a standard discretization of the problem combined with a reduced integration of the stress tensor. For this reason, the following conjecture on the error estimates is proposed.

Conjecture 7

Assuming a smooth solution to problem (??), the following error estimates hold

$$\begin{aligned} \|e_w - e_w^h\|_{L^\infty(H^1(\Omega))} &\lesssim h^k, & \|\mathbf{E}_\kappa - \mathbf{E}_\kappa^h\|_{L^\infty(L^2)} &\lesssim h^k, \\ \|\mathbf{e}_\theta - \mathbf{e}_\theta^h\|_{L^\infty(H^{\text{Grad}}(\Omega, \mathbb{R}^2))} &\lesssim h^k, & \|\mathbf{e}_\gamma - \mathbf{e}_\gamma^h\|_{L^\infty(L^2)} &\lesssim h^k, \end{aligned} \tag{8.25}$$

where the notation $a \lesssim b$ means $a \leq Cb$. The constant C depends only on the true solution and on the final time.

To validate the method first we test a finite element combinations on an analytic solution. Constructing an analytical solution for a vibrating Mindlin plate is far from trivial. Therefore, the solution for the static case [BadVMR13] is exploited.

Step 1 Consider a distributed static force given by

$$\begin{aligned} f_s(x, y) = & \frac{E_Y}{12(1-\nu^2)} \{12y(y-1)(5x^2-5x+1) \\ & \times [2y^2(y-1)2 + x(x-1)(5y^2-5y+1)] + 12x(x-1) \\ & \times (5y^2-5y+1)[2x^2(x-1)2 + y(y-1)(5x^2-5x+1)]\}. \end{aligned}$$

The static displacement and rotation are given by

$$\begin{aligned} w_s(x, y) = & \frac{1}{3}x^3(x-1)^3y^3(y-1)^3 - \frac{2b^2}{5(1-\nu)}[y^3(y-1)^3x(x-1)(5x^2-5x+1). \\ \theta_s(x, y) = & \begin{pmatrix} y^3(y-1)^3 x^2(x-1)^2(2x-1) \\ x^3(x-1)^3 y^2(y-1)^2(2y-1) \end{pmatrix} \end{aligned}$$

1660 The static solution solves the following problem defined on the square domain $\Omega = (0, 1) \times$
1661 $(0, 1)$:

$$\begin{aligned} 0 = \operatorname{div} \mathbf{q}_s + f_s, \quad \mathcal{D}_b^{-1} \mathbf{M}_s &= \operatorname{Grad} \boldsymbol{\theta}_s, \\ 0 = \operatorname{Div} \mathbf{M}_s + \mathbf{q}_s, \quad D_s^{-1} \mathbf{q}_s &= \operatorname{grad} w_s - \boldsymbol{\theta}_s. \end{aligned} \quad (8.26)$$

1662 **Step 2** Given the linear nature of the system a solution for the dynamic problem is found
1663 by multiplying the static solution by a time dependent term. For simplicity a sinus function
1664 is chosen

$$w_d(x, y, t) = w_s(x, y) \sin(t), \quad \boldsymbol{\theta}_d(x, y, t) = \boldsymbol{\theta}_s(x, y) \sin(t).$$

1665 For the port-Hamiltonian system velocities are needed

$$e_w^{\text{ex}}(x, y, t) = w_s(x, y) \cos(t), \quad e_{\theta}^{\text{ex}}(x, y, t) = \boldsymbol{\theta}_s(x, y) \cos(t).$$

1666 The momenta and shear force are then defined by

$$\mathbf{M}_d = \mathbf{E}_{\kappa}^{\text{ex}} = \mathcal{D}_b \operatorname{Grad} \boldsymbol{\theta}_d, \quad \mathbf{q}_d = \mathbf{e}_{\gamma}^{\text{ex}} = D_s(\operatorname{grad} w_d - \boldsymbol{\theta}_d)$$

Step 3 Appropriate forcing terms have to be introduced (i.e. $f, \boldsymbol{\tau}$ in (8.1)). The force and torque in the dynamical case become

$$f_d = f_s \sin(t) + \rho b \partial_{tt} w_d, \quad \boldsymbol{\tau}_d = \frac{\rho b^3}{12} \partial_{tt} \boldsymbol{\theta}_d.$$

1667 Variables $(e_w^{\text{ex}}, e_{\theta}^{\text{ex}}, \mathbf{E}_{\kappa}^{\text{ex}}, e_{\gamma}^{\text{ex}})$ under excitations $(f_d, \boldsymbol{\tau}_d)$ solve problem (7.86a). The solution
1668 being smooth, the conjectured error estimates 7 should hold. The numerical values of the
1669 physical parameters are reported in Table 8.3. To integrate the equations in time a Crank-
1670 Nicholson scheme has been used. The time step is set to $\Delta t = h/10$ to have a lower impact
1671 of the time discretization error with respect to the spatial error. The final time is set to one
1672 $t_f = 1[\text{s}]$.

Plate parameters				
E	ρ	ν	K_{sh}	h
1 [Pa]	1 [kg/m ³]	0.3	5/6	0.1 [m]

Table 8.3: Physical parameters for the Mindlin plate.

$\frac{1}{h}$	$\ e_w - e_w^h\ _{L^\infty(H^1)}$		$\ e_\theta - e_\theta^h\ _{L^\infty(H^{Grad})}$		$\ \mathbf{E}_\kappa - \mathbf{E}_\kappa^h\ _{L^\infty(L^2)}$		$\ e_\gamma - e_\gamma^h\ _{L^\infty(L^2)}$	
	Error	Order	Error	Order	Error	Order	Error	Order
8	7.30e-05	—	5.52e-04	—	3.99e-08	—	9.02e-07	—
16	3.13e-05	1.22	2.26e-04	1.28	1.88e-08	1.08	5.47e-07	0.72
32	1.57e-05	0.99	1.11e-04	1.02	8.84e-09	1.09	2.94e-07	0.89
64	7.87e-06	0.99	5.57e-05	0.99	4.31e-09	1.03	1.50e-07	0.97
128	3.94e-06	0.99	2.78e-05	0.99	2.14e-09	1.01	7.55e-08	0.99

Table 8.4: Mindlin plate convergence result $k = 1$.

$\frac{1}{h}$	$\ e_w - e_w^h\ _{L^\infty(H^1)}$		$\ e_\theta - e_\theta^h\ _{L^\infty(H^{Grad})}$		$\ \mathbf{E}_\kappa - \mathbf{E}_\kappa^h\ _{L^\infty(L^2)}$		$\ e_\gamma - e_\gamma^h\ _{L^\infty(L^2)}$	
	Error	Order	Error	Order	Error	Order	Error	Order
8	9.78e-06	—	1.04e-04	—	7.30e-09	—	1.77e-07	—
16	2.53e-06	1.95	2.49e-05	2.07	1.85e-09	1.97	4.93e-08	1.84
32	6.35e-07	1.99	6.06e-06	2.04	4.63e-10	1.99	1.27e-08	1.95
64	1.58e-07	1.99	1.50e-06	2.01	1.15e-10	2.00	3.21e-09	1.98
128	3.97e-08	2.00	3.74e-07	2.00	2.89e-11	2.00	8.06e-10	1.99

Table 8.5: Mindlin plate convergence result $k = 2$.

$\frac{1}{h}$	$\ e_w - e_w^h\ _{L^\infty(H^1)}$		$\ e_\theta - e_\theta^h\ _{L^\infty(H^{Grad})}$		$\ \mathbf{E}_\kappa - \mathbf{E}_\kappa^h\ _{L^\infty(L^2)}$		$\ e_\gamma - e_\gamma^h\ _{L^\infty(L^2)}$	
	Error	Order	Error	Order	Error	Order	Error	Order
4	1.38e-06	—	1.24e-05	—	8.24e-10	—	2.24e-08	—
8	1.79e-07	2.94	1.51e-06	3.03	1.03e-10	2.99	2.90e-09	2.94
16	2.26e-08	2.98	1.88e-07	3.00	1.28e-11	3.00	3.64e-10	2.99
32	2.83e-09	2.99	2.36e-08	2.99	1.60e-12	3.00	4.54e-11	3.00
64	3.54e-10	2.99	2.95e-09	2.99	2.00e-13	3.00	5.67e-12	3.00

Table 8.6: Mindlin plate convergence result $k = 3$.

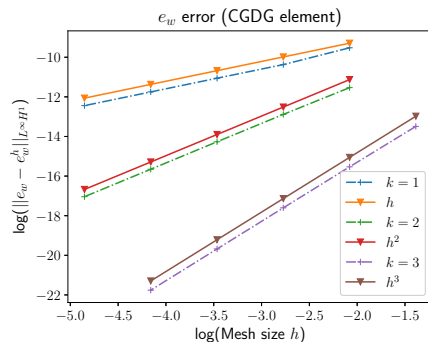
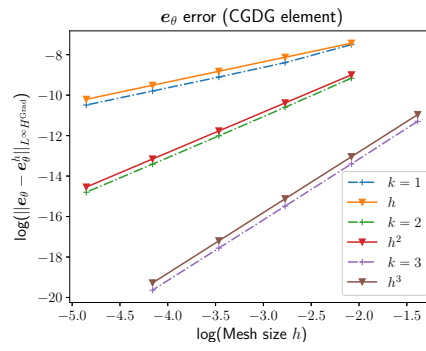
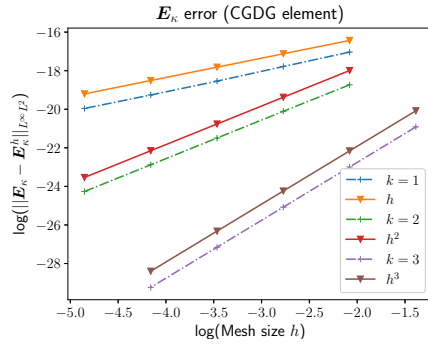
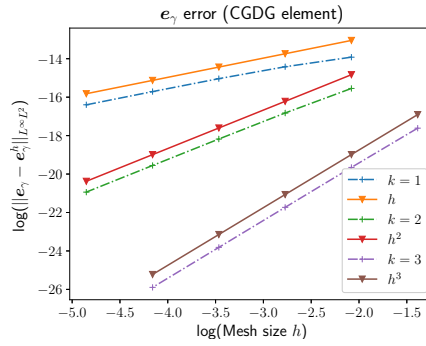
(a) $L_{\Delta t}^\infty(H^1(\Omega))$ error for e_w (b) $L_{\Delta t}^\infty(H^{\text{Grad}}(\Omega, \mathbb{R}^2))$ error for e_θ (c) $L_{\Delta t}^\infty(L^2(\Omega, \mathbb{S}))$ error for E_κ (d) $L_{\Delta t}^\infty(L^2)$ error for e_γ

Figure 8.4: Error for the Mindlin plate using the CGDG elements

Numerical applications

1676 9.1 Boundary stabilization

1677 9.2 Thermoelastic wave propagation

1678 9.3 Mixed boundary conditions

1679 9.3.1 Trajectory tracking of a thin beam

1680 9.3.2 Vibroacoustic under mixed boundary conditions

1681 9.4 Modal analysis of plates

1682

Part IV

1683

Port-Hamiltonian flexible multibody dynamics

1684

Modular multibody systems in port-Hamiltonian form

10.1 Reminder of the rigid case

10.2 Flexible floating body

10.3 Modular construction of multibody systems

1692

1693

Validation

1694

11.1 Beam systems

11.1.1 Modal analysis of a flexible mechanism

11.1.2 Non-linear crank slider

11.1.3 Hinged beam

11.2 Plate systems

11.2.1 Boundary interconnection with a rigid element

11.2.2 Actuated plate

Conclusion

Conclusions and future directions

Je n'ai cherché de rien prouver, mais de bien peindre et d'éclairer bien ma
peinture.

André Gide
Préface de L'Immoraliste

Mathematical tools

A.1 Differential operators

The space of all, symmetric and skew-symmetric $d \times d$ matrices are denoted by \mathbb{M} , \mathbb{S} , \mathbb{K} respectively. The space of \mathbb{R}^d vectors is denoted by \mathbb{V} . $\Omega \subset \mathbb{R}^d$ is an open connected set. For a scalar field $u : \Omega \rightarrow \mathbb{R}$ the gradient is defined as

$$\text{grad}(u) = \nabla u := \left(\partial_{x_1} u \dots \partial_{x_d} u \right)^\top.$$

For a vector field $\mathbf{u} : \Omega \rightarrow \mathbb{V}$, with components u_i , the gradient (Jacobian) is defined as

$$\text{grad}(\mathbf{u})_{ij} := (\nabla \mathbf{u})_{ij} = \partial_{x_i} u_j.$$

The symmetric part of the gradient operator Grad (i. e. the deformation gradient in continuum mechanics) is thus given by

$$\text{Grad}(\mathbf{u}) := \frac{1}{2} \left(\nabla \mathbf{u} + (\nabla \mathbf{u})^\top \right) \in \mathbb{S}.$$

The Hessian operator of u is then computed as follows

$$\text{Hess}(u) = \nabla^2 u = \text{Grad}(\text{grad}(u)).$$

For a tensor field $\mathbf{U} : \Omega \rightarrow \mathbb{M}$, with components u_{ij} , the divergence is a vector, defined column-wise as

$$\text{Div}(\mathbf{U}) = \nabla \cdot \mathbf{U} := \left(\sum_{i=1}^d \partial_{x_i} u_{ij} \right)_{j=1, \dots, d}.$$

The double divergence of a tensor field \mathbf{U} is then a scalar field defined as

$$\text{div}(\text{Div}(\mathbf{U})) := \sum_{i=1}^d \sum_{j=1}^d \partial_{x_i} \partial_{x_j} u_{ij}.$$

Definition 7 (Formal adjoint, Def. 5.80 [RR04])

Consider the differential operator defined on Ω

$$\mathcal{L}(\mathbf{x}, \partial) = \sum_{|\alpha| \leq k} a_\alpha(\mathbf{x}) \partial^\alpha, \quad (\text{A.1})$$

where $\alpha := (\alpha_1, \dots, \alpha_d)$ is a multi-index of order $|\alpha| := \sum_{i=1}^d \alpha_i$, a_α are a set of real scalars and $\partial^\alpha := \partial_{x_1}^{\alpha_1} \dots \partial_{x_d}^{\alpha_d}$ is a differential operator of order $|\alpha|$ resulting from a combination of spatial derivatives. The formal adjoint of \mathcal{L} is the operator defined by

$$\mathcal{L}^*(\mathbf{x}, \partial)u = \sum_{|\alpha| \leq k} (-1)^\alpha \partial^\alpha (a_\alpha(\mathbf{x})u(\mathbf{x})). \quad (\text{A.2})$$

The importance of this definition lies in the fact that

$$\langle \phi, \mathcal{L}(\mathbf{x}, \partial)\psi \rangle_\Omega = \langle \mathcal{L}^*(\mathbf{x}, \partial)\phi, \psi \rangle_\Omega \quad (\text{A.3})$$

for every $\phi, \psi \in C_0^\infty(\Omega)$. If the assumption of compact support is removed, then (A.3) no longer holds; instead the integration by parts yields additional terms involving integrals over the boundary $\partial\Omega$. However, these boundary terms vanish if ϕ and ψ satisfy certain restrictions on the boundary.

A.2 Integration by parts

Theorem 4 (Integration by parts for tensors)

Consider a smooth tensor-valued function $\mathbf{A} \in \mathbb{R}^{d \times d}$ and vector-valued function $\mathbf{b} \in \mathbb{V} = \mathbb{R}^d$. The following integration by parts formula holds

$$\int_\Omega \{\text{Div}(\mathbf{A}) \cdot \mathbf{b} + \mathbf{A} : \text{grad}(\mathbf{b})\} \, d\Omega = \int_\Omega \text{div}(\mathbf{A}\mathbf{b}) \, d\Omega = \int_{\partial\Omega} (\mathbf{A}^\top \mathbf{n}) \cdot \mathbf{b} \, dS, \quad (\text{A.4})$$

where \mathbf{n} is the outward normal at the boundary and dS the infinitesimal surface.

Proof. Consider the components expression of Eq. (A.4)

$$\begin{aligned} \int_\Omega \{\text{Div}(\mathbf{A}) \cdot \mathbf{b} + \mathbf{A} : \text{grad}(\mathbf{b})\} \, d\Omega &= \int_\Omega \sum_{i=1}^d \sum_{j=1}^d \{(\partial_{x_i} A_{ij})b_j + A_{ij}(\partial_{x_i} b_j)\} \, d\Omega, \\ &= \int_\Omega \sum_{i=1}^d \sum_{j=1}^d \partial_{x_i} (A_{ij}b_j) \, d\Omega = \int_\Omega \text{div}(\mathbf{A}\mathbf{b}) \, d\Omega, \\ &= \int_{\partial\Omega} \sum_{i=1}^d \sum_{j=1}^d (n_i A_{ij})b_j \, dS = \int_{\partial\Omega} (\mathbf{A}^\top \mathbf{n}) \cdot \mathbf{b} \, dS. \end{aligned} \quad (\text{A.5})$$

□

The previous result can be specialized for symmetric tensor field [BBF⁺13, Chapter 1].

Theorem 5 (Integration by parts for symmetric tensors)

Consider a smooth tensor-valued function $\mathbf{M} \in \mathbb{S} = \mathbb{R}_{sym}^{d \times d}$ and vector-valued function $\mathbf{b} \in \mathbb{V} =$

1729 \mathbb{R}^d . Then, it holds

$$\int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{Grad}(\mathbf{b})\} \, d\Omega = \int_{\Omega} \text{div}(\mathbf{M}\mathbf{b}) \, d\Omega = \int_{\partial\Omega} (\mathbf{M}\mathbf{n}) \cdot \mathbf{b} \, dS. \quad (\text{A.6})$$

1730 *Proof.* Consider the components expression of Eq. (A.6)

$$\int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{Grad}(\mathbf{b})\} \, d\Omega = \int_{\Omega} \sum_{i=1}^d \sum_{j=1}^d \left\{ (\partial_{x_i} M_{ij}) b_j + M_{ij} \frac{1}{2} (\partial_{x_i} b_j + \partial_{x_j} b_i) \right\} \, d\Omega, \quad (\text{A.7})$$

1731 The term $M_{ij} \frac{1}{2} (\partial_{x_i} b_j + \partial_{x_j} b_i)$ can be manipulated exploiting the symmetry of the tensor \mathbf{M}

$$\begin{aligned} \sum_{i=1}^d \sum_{j=1}^d \frac{1}{2} (M_{ij} \partial_{x_i} b_j + M_{ij} \partial_{x_j} b_i) &= \sum_{i=1}^d \sum_{j=1}^d \frac{1}{2} (M_{ij} \partial_{x_i} b_j + M_{ji} \partial_{x_i} b_j), \\ &= \sum_{i=1}^d \sum_{j=1}^d \frac{1}{2} (M_{ij} + M_{ji}) \partial_{x_i} b_j \quad \text{Since } \mathbf{M} \text{ is symmetric,} \\ &= \sum_{i=1}^d \sum_{j=1}^d M_{ij} \partial_{x_i} b_j = \mathbf{M} : \text{grad}(\mathbf{b}) \end{aligned} \quad (\text{A.8})$$

1732 Then it holds

$$\int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{Grad}(\mathbf{b})\} \, d\Omega = \int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{grad}(\mathbf{b})\} \, d\Omega \quad (\text{A.9})$$

1733 Using Eq (A.4) then

$$\begin{aligned} \int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{Grad}(\mathbf{b})\} \, d\Omega &= \int_{\Omega} \{\text{Div}(\mathbf{M}) \cdot \mathbf{b} + \mathbf{M} : \text{grad}(\mathbf{b})\} \, d\Omega, \\ &= \int_{\partial\Omega} (\mathbf{M}^{\top} \mathbf{n}) \cdot \mathbf{b} \, dS, \quad \text{Since } \mathbf{M} \text{ is symmetric,} \\ &= \int_{\partial\Omega} (\mathbf{M} \mathbf{n}) \cdot \mathbf{b} \, dS. \end{aligned} \quad (\text{A.10})$$

1734 This concludes the proof. \square

1735 A.3 Bilinear forms

Definition 8 (Skew-symmetric bilinear form)

A bilinear form on the Hilbert space H

$$\begin{aligned} b : H \times H &\longrightarrow \mathbb{R}, \\ (\mathbf{v}, \mathbf{u}) &\longrightarrow b(\mathbf{v}, \mathbf{u}), \end{aligned}$$

is skew-symmetric iff

$$b(\boldsymbol{v}, \boldsymbol{u}) = -b(\boldsymbol{u}, \boldsymbol{v}).$$

Finite elements gallery

1739

APPENDIX C

1740

Implementation using FEniCS and Firedrake

1741

1742

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Résumé — Malgré l’abondante littérature sur le formalisme pH, les problèmes d’élasticité en deux ou trois dimensions géométriques n’ont presque jamais été considérés. Cette thèse vise à étendre l’approche port-Hamiltonienne (pH) à la mécanique des milieux continus. L’originalité apportée réside dans trois contributions majeures. Tout d’abord, la nouvelle formulation pH des modèles de plaques et des phénomènes thermoélastiques couplés est présentée. L’utilisation du calcul tensoriel est obligatoire pour modéliser les milieux continus et l’introduction de variables tensorielles est nécessaire pour obtenir une description pH équivalente qui soit intrinsèque, c’est-à-dire indépendante des coordonnées choisies. Deuxièmement, une technique de discrétisation basée sur les éléments finis et capable de préserver la structure du problème de la dimension infinie au niveau discret est développée et validée. La discrétisation des problèmes d’élasticité nécessite l’utilisation d’éléments finis non standard. Néanmoins, l’implémentation numérique est réalisée grâce à des bibliothèques open source bien établies, fournissant aux utilisateurs externes un outil facile à utiliser pour simuler des systèmes flexibles sous forme pH. Troisièmement, une nouvelle formulation pH de la dynamique multicorps flexible est dérivée. Cette reformulation, valable sous de petites hypothèses de déformations, inclut toutes sortes de modèles élastiques linéaires et exploite la modularité intrinsèque des systèmes pH.

Mots clés : Systèmes port-Hamiltonien, mécanique des solides, discretisation symplectique, méthode des éléments finis, dynamique multicorps

Abstract — Despite the large literature on pH formalism, elasticity problems in higher geometrical dimensions have almost never been considered. This work establishes the connection between port-Hamiltonian distributed systems and elasticity problems. The originality resides in three major contributions. First, the novel pH formulation of plate models and coupled thermoelastic phenomena is presented. The use of tensor calculus is mandatory for continuum mechanical models and the inclusion of tensor variables is necessary to obtain an equivalent and intrinsic, i.e. coordinate free, pH description. Second, a finite element based discretization technique, capable of preserving the structure of the infinite-dimensional problem at a discrete level, is developed and validated. The discretization of elasticity problems requires the use of non-standard finite elements. Nevertheless, the numerical implementation is performed thanks to well-established open-source libraries, providing external users with an easy to use tool for simulating flexible systems in pH form. Third, flexible multibody systems are recast in pH form by making use of a floating frame description valid under small deformations assumptions. This reformulation include all kinds of linear elastic models and exploits the intrinsic modularity of pH systems.

Keywords: Port-Hamiltonian systems, continuum mechanics, structure preserving discretization, finite element method, multibody dynamics.
