

Chapter 1

Demo problem: Boundary-driven elastic deformation of a fish-shaped domain

Detailed documentation to be written. Here's a plot of the result and the already fairly well documented driver code...

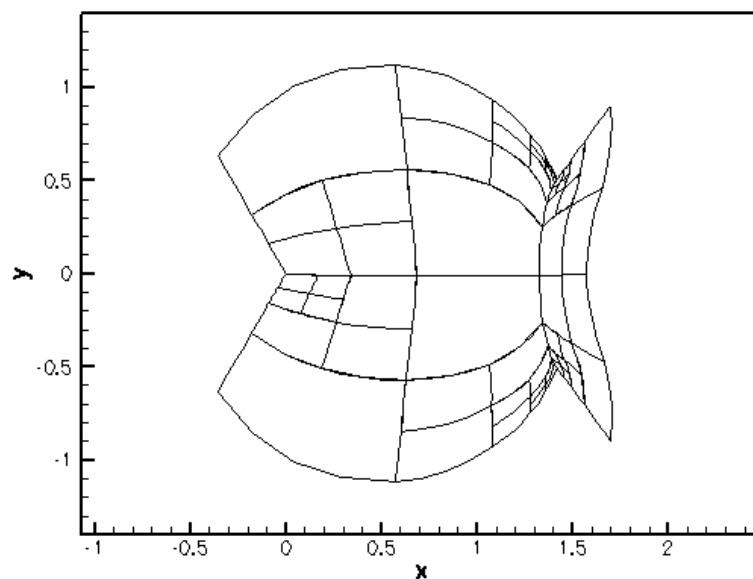


Figure 1.1 Boundary-driven elastic deformation of a fish-shaped domain.

```
//LIC// =====
//LIC// This file forms part of oomph-lib, the object-oriented,
//LIC// multi-physics finite-element library, available
//LIC// at http://www.oomph-lib.org.
//LIC//
//LIC// Version 1.0; svn revision $LastChangedRevision$
//LIC//
//LIC// $LastChangedDate$
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```

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//LIC//
//LIC//=====
// Driver for elastic deformation of a fish-shaped domain with
// adaptivity -- deformation is driven by displacement of
// GeomObject-based boundary!

// Generic oomph-lib headers
#include "generic.h"

// Solid mechanics
#include "solid.h"

// The fish mesh
#include "meshes/fish_mesh.h"

using namespace std;

using namespace oomph;

////////////////////////////////////
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//=====
/// Refineable fish mesh upgraded to become a solid mesh
//=====
template<class ELEMENT>
class ElasticFishMesh : public virtual RefineableFishMesh<ELEMENT>,
                        public virtual SolidMesh
{
public:

    /// \short Constructor: Build underlying adaptive fish mesh and then
    /// set current Eulerian coordinates to be the Lagrangian ones.
    /// Pass pointer to geometric objects that specify the
    /// fish's back in the "current" and "undeformed" configurations,
    /// and pointer to timestepper (defaults to Static)
    /// Note: FishMesh is virtual base and its constructor is automatically
    /// called first! --> this is where we need to build the mesh;
    /// the constructors of the derived meshes don't call the
    /// base constructor again and simply add the extra functionality.
    ElasticFishMesh(GeomObject* back_pt, GeomObject* undeformed_back_pt,
                    TimeStepper* time_stepper_pt=&Mesh::Default_TimeStepper) :
        FishMesh<ELEMENT>(back_pt,time_stepper_pt),
        RefineableFishMesh<ELEMENT>(back_pt,time_stepper_pt)
    {
        // Mesh has been built, adaptivity etc has been set up -->
        // assign the Lagrangian coordinates so that the current
        // configuration becomes the stress-free initial configuration
        set_lagrangian_nodal_coordinates();

        // Build "undeformed" domain: This is a "deep" copy of the
        // Domain that we used to create set the Eulerian coordinates
        // in the initial mesh -- the original domain (accessible via
        // the private member data Domain_pt) will be used to update
        // the position of the boundary nodes; the copy that we're
        // creating here will be used to determine the Lagrangian coordinates
        // of any newly created SolidNodes during mesh refinement
        double xi_nose = this->Domain_pt->xi_nose();
        double xi_tail = this->Domain_pt->xi_tail();
        Undeformed_domain_pt=new FishDomain(undeformed_back_pt,xi_nose,xi_tail);

        // Loop over all elements and set the undeformed macro element pointer
        unsigned n_element=this->nelement();
        for (unsigned e=0;e<n_element;e++)
        {
            // Get pointer to full element type
            ELEMENT* el_pt=dynamic_cast<ELEMENT*>(this->element_pt(e));

            // Set pointer to macro element so the curvilinear boundaries
            // of the undeformed mesh/domain get picked up during adaptive
            // mesh refinement
            el_pt->set_undeformed_macro_elem_pt(

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        Undeformed_domain_pt->macro_element_pt(e));

    // Use MacroElement representation for
    // Lagrangian coordinates of newly created
    // nodes
    el_pt->enable_use_of_undeformed_macro_element_for_new_lagrangian_coords();
}

/// Destructor: Kill "undeformed" Domain
virtual ~ElasticFishMesh()
{
    delete Undeformed_domain_pt;
}

private:

    /// Pointer to "undeformed" Domain -- used to determine the
    /// Lagrangian coordinates of any newly created SolidNodes during
    /// Mesh refinement
    Domain* Undeformed_domain_pt;

};

////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////
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//=====
/// Global variables
//=====
namespace Global_Physical_Variables
{
    /// Pointer to strain energy function
    StrainEnergyFunction* Strain_energy_function_pt;

    /// Pointer to constitutive law
    ConstitutiveLaw* Constitutive_law_pt;

    /// Elastic modulus
    double E=1.0;

    /// Poisson's ratio
    double Nu=0.3;

    /// "Mooney Rivlin" coefficient for generalised Mooney Rivlin law
    double C1=1.3;

    /// Body force
    double Gravity=0.0;

    /// Body force vector: Vertically downwards with magnitude Gravity
    void body_force(const double& t,
                    const Vector<double>& xi,
                    Vector<double>& b)
    {
        b[0]=0.0;
        b[1]=-Gravity;
    }
}

////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////////
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//=====
/// Boundary-driven elastic deformation of fish-shaped domain.
//=====
template<class ELEMENT>
class ElasticFishProblem : public Problem
{
public:

    /// Constructor:

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ElasticFishProblem();

/// Run simulation.
void run();

/// Access function for the mesh
ElasticFishMesh<ELEMENT>* mesh_pt()
{return dynamic_cast<ElasticFishMesh<ELEMENT>*>(Problem::mesh_pt());}

/// Doc the solution
void doc_solution(DocInfo& doc_info);

/// Update function (empty)
void actions_after_newton_solve() {}

/// \short Update before solve: We're dealing with a static problem so
/// the nodal positions before the next solve merely serve as
/// initial conditions. For meshes that are very strongly refined
/// near the boundary, the update of the displacement boundary
/// conditions (which only moves the SolidNodes *on* the boundary),
/// can lead to strongly distorted meshes. This can cause the
/// Newton method to fail --> the overall method is actually more robust
/// if we use the nodal positions as determined by the Domain/MacroElement-
/// based mesh update as initial guesses.
void actions_before_newton_solve()
{
    bool update_all_solid_nodes=true;
    mesh_pt()->node_update(update_all_solid_nodes);
}

/// Update after adapt: Pin all redundant pressure nodes (if required)
void actions_after_adapt()
{
    // Pin the redundant solid pressures (if any)
    PVDEquationsBase<2>::pin_redundant_nodal_solid_pressures(
        mesh_pt()->element_pt());
}

private:

    // Geometric object that represents the deformable fish back
    Circle* Fish_back_pt;

};

//=====
/// Constructor:
//=====
template<class ELEMENT>
ElasticFishProblem<ELEMENT>::ElasticFishProblem()
{

    // Set coordinates and radius for the circle that will become the fish back
    double x_c=0.5;
    double y_c=0.0;
    double r_back=1.0;

    // Build geometric object that will become the deformable fish back
    //GeomObject* fish_back_pt=new ElasticFishBackElement(x_c,y_c,r_back);
    Fish_back_pt=new Circle(x_c,y_c,r_back);

    // Build geometric object that specifies the fish back in the
    // undeformed configuration (basically a deep copy of the previous one)
    GeomObject* undeformed_fish_back_pt=new Circle(x_c,y_c,r_back);

    // Build fish mesh with geometric objects that specify the deformable
    // and undeformed fish back
    Problem::mesh_pt()=new ElasticFishMesh<ELEMENT>(Fish_back_pt,
                                                    undeformed_fish_back_pt);

    // Set error estimator
    Z2ErrorEstimator* error_estimator_pt=new Z2ErrorEstimator;
    mesh_pt()->spatial_error_estimator_pt()=error_estimator_pt;

    // Change/doc targets for mesh adaptation
    mesh_pt()->max_permitted_error()=0.05;
    mesh_pt()->min_permitted_error()=0.005;
    mesh_pt()->doc_adaptivity_targets(cout);

    // Pin all nodal positions apart from those on the tail
    unsigned num_bound = mesh_pt()->nboundary();
    for(unsigned ibound=0; ibound<num_bound; ibound++)
    {
        if (ibound!=2)
        {
            unsigned num_nod=mesh_pt()->nboundary_node(ibound);

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        for (unsigned inod=0; inod<num_nod; inod++)
        {
            for (unsigned i=0; i<2; i++)
            {
                mesh_pt()->boundary_node_pt(ibound, inod)->pin_position(i);
            }
        }
    }
}

//Loop over the elements in the mesh to set parameters/function pointers
unsigned n_element = mesh_pt()->nelement();
for(unsigned i=0; i<n_element; i++)
{
    //Cast to a solid element
    ELEMENT *el_pt = dynamic_cast<ELEMENT*>(mesh_pt()->element_pt(i));

    // Set the constitutive law
    el_pt->constitutive_law_pt() =
        GlobalPhysicalVariables::Constitutive_law_pt;

    // Set the body force
    el_pt->body_force_fct_pt()=GlobalPhysicalVariables::body_force;

}

// Pin the redundant solid pressures (if any)
PVDEquationsBase<2>::pin_redundant_nodal_solid_pressures(
    mesh_pt()->element_pt());

//Attach the boundary conditions to the mesh
cout << assign_eqn_numbers() << std::endl;

// Refine the problem uniformly (this automatically passes the
// function pointers/parameters to the finer elements
refine_uniformly();

// The non-pinned positions of the newly SolidNodes will have been
// determined by interpolation. Update all solid nodes based on
// the Mesh's Domain/MacroElement representation.
bool update_all_solid_nodes=true;
mesh_pt()->node_update(update_all_solid_nodes);

// Now set the Eulerian equal to the Lagrangian coordinates
mesh_pt()->set_lagrangian_nodal_coordinates();

}

//=====
/// Doc the solution
//=====
template<class ELEMENT>
void ElasticFishProblem<ELEMENT>::doc_solution(DocInfo& doc_info)
{
    ofstream some_file;
    char filename[100];

    // Number of plot points
    unsigned npts = 5;

    // Output shape of deformed body
    sprintf(filename, "%s/soln%i.dat", doc_info.directory().c_str(),
        doc_info.number());
    some_file.open(filename);
    mesh_pt()->output(some_file, npts);
    some_file.close();

    // removed until Jacobi eigensolver is re-instated
    // // Output principal stress vectors at the centre of all elements
    // SolidHelpers::doc_2D_principal_stress<ELEMENT>(doc_info, mesh_pt());

}

//=====
/// Run the problem
//=====
template<class ELEMENT>
void ElasticFishProblem<ELEMENT>::run()
{
    // Output
    DocInfo doc_info;

    // Set output directory

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doc_info.set_directory("RESULT");

// Step number
doc_info.number()=0;

// Initial parameter values

// Gravity:
Global_Physical_Variables::Gravity=0.1;

//Parameter incrementation
unsigned nstep=5;
for(unsigned i=0;i<nstep;i++)
{
    //Solve the problem with Newton's method, allowing for up to 5
    //rounds of adaptation
    newton_solve(5);

    // Doc solution
    doc_solution(doc_info);
    doc_info.number()++;

    // Increment width
    Fish_back_pt->y_c()+=0.03;
}

}

//=====
/// Driver for simple elastic problem
//=====
int main()
{

    //Initialise physical parameters
    Global_Physical_Variables::E = 2.1;
    Global_Physical_Variables::Nu = 0.4;
    Global_Physical_Variables::C1 = 1.3;

    // Define a strain energy function: Generalised Mooney Rivlin
    Global_Physical_Variables::Strain_energy_function_pt =

        new GeneralisedMooneyRivlin(&Global_Physical_Variables::Nu,
                                    &Global_Physical_Variables::C1,
                                    &Global_Physical_Variables::E);

    // Define a constitutive law (based on strain energy function)
    Global_Physical_Variables::Constitutive_law_pt =
        new IsotropicStrainEnergyFunctionConstitutiveLaw(
            Global_Physical_Variables::Strain_energy_function_pt
        );

    //Set up the problem with pure displacement formulation
    ElasticFishProblem<RefineableQPVDElement<2,3> > problem;
    problem.run();

}

```

1.1 PDF file

A [pdf version](#) of this document is available.