

Lecture 2 - Tensor review, Anisotropic Elasticity

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schedule

- Feb 4 - Tensor review, Anisotropic Elasticity
- Feb 9 - Coordinate Transformation
- Feb 11 - 1D Micromechanics (HW1 Due)
- Feb 16 - Orientation Averaging

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- index notation
- anisotropic elasticity

index notation

index notation

- Consider the following
- $s = a_1x_1 + a_2x_2 + \dots + a_nx_n$
- Which we could also write as

$$s = \sum_{i=1}^n a_i x_i$$

- Using index notation, and Einstein's summation convention, we can also write this as $s = a_i x_i$

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dummy index

- In index notation, a repeated index implies summation
- This index is also referred to as a dummy index
- It is called a “dummy index” because the expression would have the same meaning with any index in its place
- i.e. i, j, k , etc. would all have the same meaning when repeated

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dummy index

- Note, no index may be repeated more than once, thus the expression

$$s = \sum_{i=1}^n a_i b_i x_i$$

could not be directly written in index notation

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free index

- Any index which is not repeated in an index notation expression is referred to as a free index
- The number of free indexes in an expression indicate the tensor order of that expression
- No free indexes = scalar expression (0-order tensor)
- One free index = vector expression (1st-order tensor)
- Two free indexes = matrix expression (2nd-order tensor)

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index notation

- Free index is not repeated (on any term)
- Free index takes all values (1,2,3)
- e.g. $u_i = \langle u_1, u_2, u_3 \rangle$
- Free indexes must match across terms in an expression or equation

Dummy index is repeated on at least one term
Dummy index indicates summation over all values e.g. $\sigma_{ii} = \sigma_{11} + \sigma_{22} + \sigma_{33}$
Index can not be used more than twice in the same term
($A_{ij}B_{jk}C_{kl}$ is good, $A_{ij}B_{ij}C_{ij}$ is not)

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dummy index

- The dummy index can be triggered by any repeated index in a *term*.
- Summation or not?
 - $a_i + b_{ij}c_j$
 - $a_{ij}b_{ij}$
 - $a_{ij} + b_{ij}c_j$

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- How can we write matrix multiplication in index notation?

$$\begin{bmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \end{bmatrix} \begin{bmatrix} b_{11} & b_{12} \\ b_{21} & b_{22} \end{bmatrix} = \begin{bmatrix} c_{11} & c_{12} \\ c_{21} & c_{22} \end{bmatrix}$$

special symbols

- For convenience we define two symbols in index notation
- *Kronecker delta* is a general tensor form of the Identity Matrix

$$\delta_{ij} = \begin{cases} 1 & \text{if } i = j \\ 0 & \text{otherwise} \end{cases} = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

- Is also used for higher order tensors

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- $\delta_{ij} = \delta_{ji}$
- $\delta_{ii} = 3$
- $\delta_{ij}a_j = a_i$
- $\delta_{ij}b_{ij} = b_{ii}$

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alternating symbol

- *alternating symbol or permutation symbol*

$$\epsilon_{ijk} = \begin{cases} 1 & \text{if } ijk \text{ is an even permutation of } 1,2,3 \\ -1 & \text{if } ijk \text{ is an odd permutation of } 1,2,3 \\ 0 & \text{otherwise} \end{cases}$$

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alternating symbol

- This symbol is not used as frequently as the *Kronecker delta*
- For our uses in this course, it is enough to know that 123, 231, and 312 are even permutations
- 321, 132, 213 are odd permutations
- all other indexes are zero
- $\epsilon_{ijk}\epsilon_{imn} = \delta_{jm}\delta_{kn} - \delta_{jn}\delta_{mk}$

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tensor algebra

substitution

- When solving tensor equations, we often need to manipulate expressions
- We need to make sure the correct indexes are used when substituting, for example

$$a_i = U_{im}b_m \quad (1)$$

$$b_i = V_{im}c_m \quad (2)$$

- To substitute (2) into (1), we first need to change indexes

substitution

- We need to change the free index, i , to m in (2)
- Since m is already used as the dummy index, we need to change that too

$$b_m = V_{mj}c_j \quad (3)$$

- We can now make the substitution

$$a_i = U_{im}V_{mj}c_j \quad (4)$$

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multiplication

- We need to be careful with indexes when multiplying expressions
- $p = a_mb_m$ and $q = c_md_m$
- We can express, pq , but remember the dummy index cannot be repeated more than once
- $pq \neq a_mb_mc_md_m$
- Instead we must change the dummy index in one of the expressions first
- $pq = a_mb_mc_nd_n$

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- In the following expression, we would like to factor out n , but it has different indexes
- $\sigma_{ij}n_j - \lambda n_i = 0$
- Recall $\delta_{ij}a_j = a_i$ we can rewrite $n_i = \delta_{ij}n_j$
- $\sigma_{ij}n_j - \lambda\delta_{ij}n_j = 0$
- $(\sigma_{ij} - \lambda\delta_{ij})n_j = 0$

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contraction

- σ_{ii} is the contraction of σ_{ij}
- This can often be a useful tool in solving tensor equations
- $\sigma_{ij} = \lambda\Delta\delta_{ij} + 2\mu E_{ij}$
- $\sigma_{ii} = 3\lambda\Delta + 2\mu E_{ii}$

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tensor calculus

partial derivative

- We indicate (partial) derivatives using a comma
- In three dimensions, we take the partial derivative with respect to each variable (x , y , z or x_1 , x_2 , and x_3)
- For example a scalar property, such as density, can have a different value at any point in space
- $\rho = \rho(x_1, x_2, x_3)$
- $\rho_{,i} = \frac{\partial}{\partial x_i} \rho = \left\langle \frac{\partial \rho}{\partial x_1}, \frac{\partial \rho}{\partial x_2}, \frac{\partial \rho}{\partial x_3} \right\rangle$

- Similarly, if we take the partial derivative of a vector, it produces a matrix

$$u_{i,j} = \frac{\partial}{\partial x_j} u_i = \begin{bmatrix} \frac{\partial u_1}{\partial x_1} & \frac{\partial u_1}{\partial x_2} & \frac{\partial u_1}{\partial x_3} \\ \frac{\partial u_2}{\partial x_1} & \frac{\partial u_2}{\partial x_2} & \frac{\partial u_2}{\partial x_3} \\ \frac{\partial u_3}{\partial x_1} & \frac{\partial u_3}{\partial x_2} & \frac{\partial u_3}{\partial x_3} \end{bmatrix}$$

dyadic notation

- Dyadic notation is sometimes called tensor product notation
- Dyadic product: $C_{ij} = a_i b_j$ is written as $C = a \otimes b$
- Double dot product: $A_{ij} B_{ji} = c$ is written as $A : B = c$

transformation

linear transformation

- Let us consider some transformation, \mathbf{T} , which transforms any vector into another vector
- If we transform $\mathbf{T} a = c$ and $\mathbf{T} b = d$
- We call \mathbf{T} a linear transformation (and a tensor) if

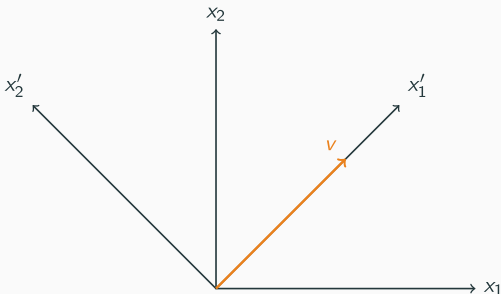
$$\mathbf{T}(\mathbf{a} + \mathbf{b}) = \mathbf{T}\mathbf{a} + \mathbf{T}\mathbf{b}$$

$$\mathbf{T}(\alpha\mathbf{a}) = \alpha\mathbf{T}\mathbf{a}$$

- Where α is any arbitrary scalar and a, b are arbitrary vectors

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coordinate transformation in two dimensions



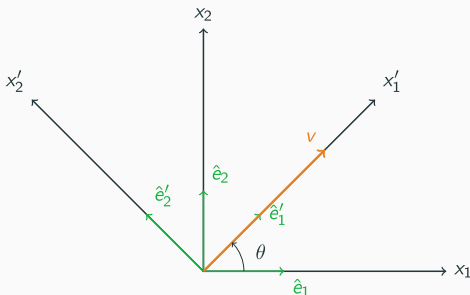
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coordinate transformation in two dimensions

- The vector, v , remains fixed, but we transform our coordinate system
- In the new coordinate system, the x'_2 portion of v is zero.
- To transform the coordinate system, we first define some unit vectors.
- \hat{e}_1 is a unit vector in the direction of x_1 , while \hat{e}'_1 is a unit vector in the direction of x'_1

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coordinate transformation in two dimensions



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coordinate transformation in two dimensions

- For this example, let us assume $v = \langle 2, 2 \rangle$ and $\theta = 45^\circ$
- We can write the transformed unit vectors, \hat{e}'_1 and \hat{e}'_2 in terms of \hat{e}_1 , \hat{e}_2 and the angle of rotation, θ .

$$\hat{e}'_1 = \langle \hat{e}_1 \cos \theta, \hat{e}_2 \sin \theta \rangle$$

$$\hat{e}'_2 = \langle -\hat{e}_1 \sin \theta, \hat{e}_2 \cos \theta \rangle$$

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coordinate transformation in two dimensions

- We can write the vector, v , in terms of the unit vectors describing our axis system
- $v = v_1 \hat{e}_1 + v_2 \hat{e}_2$
- (note: $\hat{e}_1 = \langle 1, 0 \rangle$ and $\hat{e}_2 = \langle 0, 1 \rangle$)
- $v = \langle 2, 2 \rangle = 2\langle 1, 0 \rangle + 2\langle 0, 1 \rangle$

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- When expressed in the transformed coordinate system, we refer to v'
- $v' = \langle v_1 \cos \theta + v_2 \sin \theta, -v_1 \sin \theta + v_2 \cos \theta \rangle$
- $v' = \langle 2\sqrt{2}, 0 \rangle$
- We can recover the original vector from the transformed coordinates:
- $v = v'_1 \hat{e}'_1 + v'_2 \hat{e}'_2$
- (note: $\hat{e}'_1 = \langle \frac{\sqrt{2}}{2}, \frac{\sqrt{2}}{2} \rangle$ and $\hat{e}'_2 = \langle -\frac{\sqrt{2}}{2}, \frac{\sqrt{2}}{2} \rangle$)
- $v = 2\sqrt{2} \langle \frac{\sqrt{2}}{2}, \frac{\sqrt{2}}{2} \rangle + 0 \langle -\frac{\sqrt{2}}{2}, \frac{\sqrt{2}}{2} \rangle = \langle 2, 2 \rangle$

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general coordinate transformation

- Coordinate transformation can become much more complicated in three dimensions, and with higher-order tensors
- It is convenient to define a general form of the coordinate transformation in index notation
- We define Q_{ij} as the cosine of the angle between the x'_i axis and the x_j axis.
- This is also referred to as the “direction cosine”

$$Q_{ij} = \cos(x'_i, x_j)$$

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- Different textbooks flip the definition of Q_{ij} (Elasticity and Continuum texts have opposite definitions, for example)
- The result gives the transpose
- Always use equations (next slide) from the same source as your Q_{ij} definition

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general coordinate transformation

- We can transform any-order tensor using Q_{ij}
- Vectors (first-order tensors): $v'_i = Q_{ij}v_j$
- Matrices (second-order tensors): $\sigma'_{ij} = Q_{im}Q_{jn}\sigma_{mn}$
- Fourth-order tensors: $C'_{ijkl} = Q_{im}Q_{jn}Q_{ko}Q_{lp}C_{mnop}$

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general coordinate transformation

- We can use this form on our 2D transformation example

$$\begin{aligned} Q_{ij} &= \cos(x'_i, x_j) \\ &= \begin{bmatrix} \cos(x'_1, x_1) & \cos(x'_1, x_2) \\ \cos(x'_2, x_1) & \cos(x'_2, x_2) \end{bmatrix} \\ &= \begin{bmatrix} \cos \theta & \cos(90 - \theta) \\ \cos(90 + \theta) & \cos \theta \end{bmatrix} \\ &= \begin{bmatrix} \cos \theta & \sin \theta \\ -\sin \theta & \cos \theta \end{bmatrix} \end{aligned}$$

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general coordinate transformation

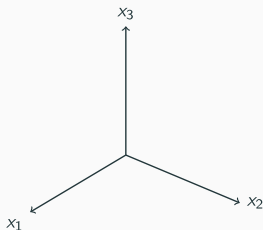
- We can similarly use Q_{ij} to find tensors in the original coordinate system
- Vectors (first-order tensors): $v_j = Q_{ij} v'_i$
- Matrices (second-order tensors): $\sigma_{mn} = Q_{im} Q_{jn} \sigma'_{ij}$
- Fourth-order tensors: $C_{mnop} = Q_{im} Q_{jn} Q_{ko} Q_{lp} C'_{ijkl}$

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- We can derive some interesting properties of the transformation tensor, Q_{ij}
- We know that $v'_i = Q_{ij}v_j$ and that $v_j = Q_{ij}v'_i$
- If we substitute (changing the appropriate indexes) we find:
- $v_j = Q_{ij}Q_{ik}v_k$
- We can now use the Kronecker Delta to substitute
 $v_j = \delta_{jk}v_k$
- $\delta_{jk}v_k = Q_{ij}Q_{ik}v_k$

examples

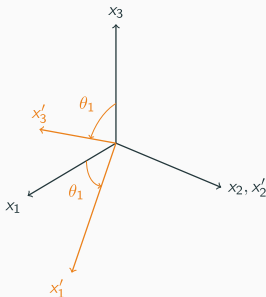
example



- Find Q_{ij}^1 for rotation of 60° about x_2
- Find Q_{ij}^2 for rotation of 30° about x_3'
- Find e_i'' after both rotations

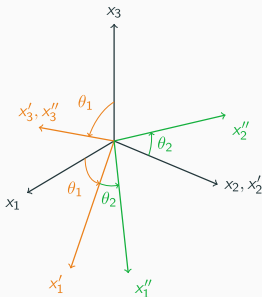
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example



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example



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example

- $Q_{ij}^1 = \cos(x'_i, x_j)$
- $Q_{ij}^2 = \cos(x''_i, x'_j)$

$$Q_{ij}^1 = \begin{bmatrix} \cos 60 & \cos 90 & \cos 150 \\ \cos 90 & \cos 0 & \cos 90 \\ \cos 30 & \cos 90 & \cos 60 \end{bmatrix}$$

$$Q_{ij}^2 = \begin{bmatrix} \cos 30 & \cos 60 & \cos 90 \\ \cos 120 & \cos 30 & \cos 90 \\ \cos 90 & \cos 90 & \cos 0 \end{bmatrix}$$

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- We now use Q_{ij} to find \hat{e}'_i and \hat{e}''_i
- First, we need to write \hat{e}_i in a manner more consistent with index notation
- We will indicate axis direction with a superscript, e.g. $\hat{e}_1 = e_i^1$
- $e'_i = Q_{ij}^1 e_j$
- $e''_i = Q_{ij}^2 e'_j$
- How do we find e''_i in terms of e_i ?

anisotropic elasticity

- In 3D, Hooke's Law for linearly elastic materials is

$$\sigma_{ij} = C_{ijkl}\epsilon_{kl}$$

- For isotropic materials, C_{ijkl} can be expressed in terms of two constants
- In general (anisotropic materials) more constants are needed and we use the full tensor

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engineering notation

- Fourth-order tensors are cumbersome to write, we often use engineering notation
- σ and ϵ are written as vectors and C_{ijkl} is written as a matrix.
- NOTE: Although σ , ϵ and C_{ijkl} are tensors, their counterparts in engineering notation are NOT formal tensors
- This means that the usual transformation laws do not apply

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$$\begin{bmatrix} \sigma_{11} \\ \sigma_{22} \\ \sigma_{33} \\ \sigma_{23} \\ \sigma_{13} \\ \sigma_{12} \end{bmatrix} = \begin{bmatrix} C_{1111} & C_{1122} & C_{1133} & C_{1123} & C_{1113} & C_{1112} \\ C_{1122} & C_{2222} & C_{2233} & C_{2223} & C_{1322} & C_{1222} \\ C_{1133} & C_{2233} & C_{3333} & C_{2333} & C_{1333} & C_{1233} \\ C_{1123} & C_{2223} & C_{2333} & C_{2323} & C_{1323} & C_{1223} \\ C_{1113} & C_{1322} & C_{1333} & C_{1323} & C_{1313} & C_{1213} \\ C_{1112} & C_{1222} & C_{1233} & C_{1223} & C_{1213} & C_{1212} \end{bmatrix} \begin{bmatrix} E_{11} \\ E_{22} \\ E_{33} \\ E_{23} \\ 2E_{13} \\ 2E_{12} \end{bmatrix}$$

compliance

$$\begin{bmatrix} E_{11} \\ E_{22} \\ E_{33} \\ E_{23} \\ 2E_{13} \\ 2E_{12} \end{bmatrix} = \begin{bmatrix} S_{1111} & S_{1122} & S_{1133} & S_{1123} & S_{1113} & S_{1112} \\ S_{1122} & S_{2222} & S_{2233} & S_{2223} & S_{1322} & S_{1222} \\ S_{1133} & S_{2233} & S_{3333} & S_{2333} & S_{1333} & S_{1233} \\ S_{1123} & S_{2223} & S_{2333} & S_{2323} & S_{1323} & S_{1223} \\ S_{1113} & S_{1322} & S_{1333} & S_{1323} & S_{1313} & S_{1213} \\ S_{1112} & S_{1222} & S_{1233} & S_{1223} & S_{1213} & S_{1212} \end{bmatrix} \begin{bmatrix} \sigma_{11} \\ \sigma_{22} \\ \sigma_{33} \\ \sigma_{23} \\ \sigma_{13} \\ \sigma_{12} \end{bmatrix}$$

- If we now consider the case of uniaxial tension, we see that

$$E_{11} = S_{1111}\sigma_{11}$$

$$E_{22} = S_{1122}\sigma_{11}$$

$$E_{33} = S_{1133}\sigma_{11}$$

$$2E_{23} = S_{1123}\sigma_{11}$$

$$2E_{13} = S_{1113}\sigma_{11}$$

$$2E_{12} = S_{1112}\sigma_{11}$$

- S_{1111} is familiar, acting like $1/EY$

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poisson's ratio

- For isotropic materials we defined Poisson's ratio as $\nu = -E_{22}/E_{11}$
- For anisotropic materials, we can have a different Poisson's ratio acting in different directions
- We define $\nu_{ij} = -E_{jj}/E_{ii}$ (with no summation), the ratio of the transverse strain in the j direction when stress is applied in the i direction
- For this example we can find ν_{12} and ν_{13} as

$$\nu_{12} = -E_{22}/E_{11} = -S_{1122}/S_{1111}$$

$$\nu_{13} = -E_{33}/E_{11} = -S_{1133}/S_{1111}$$

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- Note that we cannot, in general, say that $\nu_{12} = \nu_{21}$
- However, due to the symmetry of the stiffness/compliance tensors, we know that

$$\nu_{21}E_x = \nu_{12}E_y$$

$$\nu_{31}E_x = \nu_{13}E_z$$

$$\nu_{32}E_y = \nu_{23}E_z$$

- Where E_x refer's to the Young's Modulus in the x -direction, etc.

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shear coupling coefficients

- An unfamiliar effect is that shear strains can be introduced from a normal stress
- We define shear coupling coefficients as $\eta_{1112} = \eta_{16} = -2E_{12}/E_{11}$ due to σ_{11}
- These coupling terms can also effect shear strain in a different plane from the applied shear stress
- Like the Poisson's ratio, these are not entirely independent

$$\eta_{61}E_x = \eta_{16}G_6$$

- Where G_6 is the shear modulus in the 12 plane

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shear coupling coefficients

- Shear coupling coefficients are sometimes placed in two groups
- Coefficients of mutual influence relate shear stress to normal strain and normal stress to shear strain
- Chentsov coefficients relate shear stress in one plane to shear strain in another plane
- In general we can say

$$\eta_{nm}E_m = \eta_{mn}G_n \quad (m = 1,2,3) \quad (n = 4,5,6)$$

and

$$\eta_{nm}G_m = \eta_{mn}G_n \quad (m,n = 4,5,6) \quad m \neq n$$

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orthotropic symmetry

$$\begin{bmatrix} \sigma_{11} \\ \sigma_{22} \\ \sigma_{33} \\ \sigma_{23} \\ \sigma_{13} \\ \sigma_{12} \end{bmatrix} = \begin{bmatrix} C_{1111} & C_{1122} & C_{1133} & 0 & 0 & 0 \\ C_{1122} & C_{2222} & C_{2233} & 0 & 0 & 0 \\ C_{1133} & C_{2233} & C_{3333} & 0 & 0 & 0 \\ 0 & 0 & 0 & C_{2323} & 0 & 0 \\ 0 & 0 & 0 & 0 & C_{1313} & 0 \\ 0 & 0 & 0 & 0 & 0 & C_{1212} \end{bmatrix} \begin{bmatrix} E_{11} \\ E_{22} \\ E_{33} \\ E_{23} \\ 2E_{13} \\ 2E_{12} \end{bmatrix}$$

transversely isotropic symmetry

$$\begin{bmatrix} \sigma_{11} \\ \sigma_{22} \\ \sigma_{33} \\ \sigma_{23} \\ \sigma_{13} \\ \sigma_{12} \end{bmatrix} = \begin{bmatrix} C_{1111} & C_{1122} & C_{1133} & 0 & 0 & 0 \\ C_{1122} & C_{1111} & C_{1133} & 0 & 0 & 0 \\ C_{1133} & C_{1133} & C_{3333} & 0 & 0 & 0 \\ 0 & 0 & 0 & C_{1313} & 0 & 0 \\ 0 & 0 & 0 & 0 & C_{1313} & 0 \\ 0 & 0 & 0 & 0 & 0 & 1/2(C_{1111} - C_{2222}) \end{bmatrix} \begin{bmatrix} E_1 \\ E_2 \\ E_3 \\ E_2 \\ 2E_3 \\ 2E_1 \end{bmatrix}$$

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isotropic symmetry

$$\begin{bmatrix} \sigma_{11} \\ \sigma_{22} \\ \sigma_{33} \\ \sigma_{23} \\ \sigma_{13} \\ \sigma_{12} \end{bmatrix} = \frac{E}{(1+\nu)(1-2\nu)} \begin{bmatrix} 1-\nu & \nu & \nu & 0 & 0 & 0 \\ \nu & 1-\nu & \nu & 0 & 0 & 0 \\ \nu & \nu & 1-\nu & 0 & 0 & 0 \\ 0 & 0 & 0 & \frac{1}{2}(1-2\nu) & 0 & 0 \\ 0 & 0 & 0 & 0 & \frac{1}{2}(1-2\nu) & 0 \\ 0 & 0 & 0 & 0 & 0 & \frac{1}{2}(1-2\nu) \end{bmatrix} \begin{bmatrix} E_1 \\ E_2 \\ E_3 \\ E_2 \\ 2E_3 \\ 2E_1 \end{bmatrix}$$

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- Next class we will develop transformation laws for engineering stress/strain and stiffness