

# Parabolized Navier-Stokes Solution for Axisymmetric Ogive-Cylinder

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## 1 Introduction

Indoor builders are always interested in finding ways to improve their model flight times. I started the project [1]

## 2 Derivation of Fluid Dynamics Equations of Motion

The system of equations which govern the flow of any fluid, the familiar Navier-Stokes equations, may be derived from the concepts of conservation of mass, momentum, and energy, together with the thermodynamic state equation for the working fluid. Although this derivation is available from many sources, it is included here for easy reference in other parts of this study.

Consider an arbitrary volume of fluid,  $\mathbf{R}$ , which is enclosed within a surface,  $\mathbf{S}$ , with a unit outward normal  $\vec{\mathbf{ds}}$  as shown below:

Let the vector  $\vec{\mathbf{V}}$  describe the velocity of fluid element passing through the control volume surface at any time. Note that while the shape of  $R$  is arbitrary, it does not vary with time. Thus for any time varying function:

$$\frac{\partial}{\partial t} \iiint_R (f) dR = \iiint_R \frac{\partial f}{\partial t} dR \quad (2.1)$$

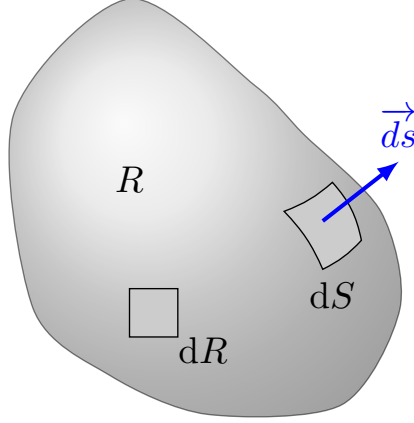


Figure 1: Control Volume

## 2.1 Conservation of Mass

Let  $\vec{V}$  be the velocity of a fluid element passing through the control volume  $R$ . We can state the principle of conservation of mass as:

The time rate of change of mass increase within the control volume  $\mathbf{R}$ , in the absence of internal sources, is equal to the net flux of mass into  $\mathbf{R}$  through the surface  $\mathbf{S}$ .

The outward component of the mass flux at any point on  $\mathbf{S}$  is given by:

$$\rho \vec{V} \cdot \vec{ds} \quad (2.2)$$

Thus, the total mass flux through  $\mathbf{S}$  is given by the integral:

$$\iint_S -(\rho \vec{V} \cdot \vec{ds}) \quad (2.3)$$

This surface integral can be converted into a volume integral by making use of the *Divergence Theorem*:

$$\iint_S \vec{q} \cdot \vec{ds} = \iiint_R (\vec{\nabla} \cdot \vec{q}) dR \quad (2.4)$$

Therefore, the mass flux becomes:

$$- \iiint_R (\vec{\nabla} \cdot \rho \vec{V}) dR \quad (2.5)$$

The conservation of mass law becomes:

$$\iiint_R \frac{\partial \rho}{\partial t} dR = - \iiint_R (\vec{\nabla} \cdot \rho \vec{V}) dR \quad (2.6)$$

or

$$\iiint_R [\vec{\nabla} \cdot \rho t + \vec{\nabla} \cdot \rho \vec{V}] dR = 0 \quad (2.7)$$

But, since the  $\mathbf{R}$  is arbitrary, the above expression will only be valid if the integrand is everywhere zero. That is:

$$\frac{\partial \rho}{\partial t} + \vec{\nabla} \cdot \rho \vec{V} = 0 \quad (2.8)$$

## 2.2 Conservation of Momentum

The conservation of momentum law is stated as follows:

The time rate of momentum increase throughout  $\mathbf{R}$  is equal to the net force acting on  $\mathbf{R}$  plus the net flux of momentum into  $\mathbf{R}$  through the surface  $\mathbf{S}$ .

The net force acting on  $\mathbf{R}$  will consist of any externally applied body force plus the forces acting on  $\mathbf{R}$  that stem from the motion of the fluid itself. These later forces are the internal stress forces acting on the fluid volume. Since any body forces will be specified, we need to find a way to describe the internal stress forces in the fluid at any point.

Stress is related to the forces exerted on a fluid particle by adjacent particles. If we cut our control volume with a plane, the force per unit area acting on one side of the plane is caused by the fluid particles on the other side of the plane. Since the stresses measured at any point will be different for each plane cut passing through that point, the minimum amount of

information necessary to completely describe the stress state at that point must be determined.

Consider an arbitrary tetrahedron with three sides joining at a point in the flow, and assume that the stress on these three sides is known. Then the condition of state equilibrium can be used to find the stress on the fourth side of this shape, regardless of the orientation of that fourth face with respect to the other three. From this argument it may be seen that the stress state at a point may be determined if the stresses on any three surfaces passing through that point are known. For convenience, these three surfaces are usually assumed to be orthogonal. Note that the three stresses are vector quantities that can be expressed as a set of vector components. Furthermore, the conditions of static equilibrium will result in a total of nine vector components, but only six are independent.

The standard way to describe the stress state at a point is to set up a stress matrix  $\tau$  that looks like this:

$$\tau = \begin{bmatrix} \tau_{xx} & \tau_{xy} & \tau_{xz} \\ \tau_{yx} & \tau_{yy} & \tau_{yz} \\ \tau_{zx} & \tau_{zy} & \tau_{zz} \end{bmatrix} \quad (2.9)$$

In this notation  $\tau_{xy}$  is the  $y$  component of the stress acting on the face perpendicular to the  $x$  axis.

The three dependent stresses are:

$$\begin{aligned} \tau_{xy} &= \tau_{yx} \\ \tau_{xz} &= \tau_{zx} \\ \tau_{yz} &= \tau_{zy} \end{aligned} \quad (2.10)$$

Therefore, the stress matrix is seen to be symmetric.

In general, as a fluid volume moves, it will both deform and rotate. If we consider two points along the path of this motion, we can use a *Taylor Series* to relate the velocity at one point to the velocity at the other. In Cartesian coordinates this becomes:

$$\begin{aligned}
U_B = U_A &+ \left( \frac{\partial U}{\partial x} \right)_A (x_B - x_A) \\
&+ \frac{1}{2} \left( \frac{\partial^2 U}{\partial x^2} \right)_A (x_B - x_A)^2 \\
&+ \left( \frac{\partial U}{\partial y} \right)_A (y_B - y_A) \\
&+ \frac{1}{2} \left( \frac{\partial^2 U}{\partial y^2} \right)_A (y_B - y_A)^2 \\
&+ \left( \frac{\partial U}{\partial z} \right)_A (z_B - z_A) \\
&+ \frac{1}{2} \left( \frac{\partial^2 U}{\partial z^2} \right)_A (z_B - z_A)^2 \\
&+ \left( \frac{\partial^2 U}{\partial x \partial y} \right)_A (x_B - x_A)(y_B - y_A) \\
&+ \left( \frac{\partial^2 U}{\partial x \partial z} \right)_A (x_B - x_A)(z_B - z_A) + \dots
\end{aligned} \tag{2.11}$$

We can write similar equations for the remaining two velocity components. If we only retain the linear terms, this reduced to:

$$U_B = U_A + \left( \frac{\partial U}{\partial x} \right)_A (x_B - x_A) + \left( \frac{\partial U}{\partial y} \right)_A (y_B - y_A) + \left( \frac{\partial U}{\partial z} \right)_A (z_B - z_A) \tag{2.12}$$

This can be expressed in matrix form as:

$$\bar{\bar{D}} = \begin{bmatrix} \frac{\partial u}{\partial x} & \frac{\partial u}{\partial y} & \frac{\partial u}{\partial z} \\ \frac{\partial v}{\partial x} & \frac{\partial v}{\partial y} & \frac{\partial v}{\partial z} \\ \frac{\partial w}{\partial x} & \frac{\partial w}{\partial y} & \frac{\partial w}{\partial z} \end{bmatrix} = \vec{\nabla} \vec{V} \tag{2.13}$$

This matrix is commonly referred to as the rate of deformation matrix. The derivatives  $\frac{\partial u}{\partial x}$ ,  $\frac{\partial v}{\partial y}$ , and  $\frac{\partial w}{\partial z}$  indicate stretching motion called dilitation. The other derivatives indicate distortion of the fluid due to shearing forces. By viewing the motion in this manner it is apparent that the stresses in the fluid characterized by the matrix  $\bar{\bar{\tau}}$  may be described by the above deformation

matrix together with the static pressure force. This analysis is known as *Stokes Theorem* for stresses and is given below

As was previously noted, the stress matrix is symmetric. One method for forming a symmetric matrix from  $\bar{\bar{D}}$  is to combine it with its transpose. Thus the stress tensor may be written as:

$$\bar{\bar{\tau}} = -P^*\bar{\mathbf{I}} + \mu(\bar{\bar{D}} + \bar{\bar{D}}^T) \quad (2.14)$$

where  $\mu$  is the bulk viscosity coefficient. It is common to define the hydrostatic pressure  $P$  as the mean value of the three normal stresses  $\tau_{xx}$ ,  $\tau_{yy}$ , and  $\tau_{zz}$ . In this case:

$$P = \frac{1}{3}\{-3P^* + 2\mu(\frac{\partial u}{\partial x} + \frac{\partial v}{\partial y} + \frac{\partial u}{\partial x})\} \quad (2.15)$$

or

$$P = -P^* + \frac{2}{3}\mu\vec{\nabla} \cdot \vec{\mathbf{V}} = -P^* - \lambda\vec{\nabla} \cdot \vec{\mathbf{V}} \quad (2.16)$$

Therefore:

$$\bar{\bar{\tau}} = -P\bar{\bar{I}} + \lambda\vec{\nabla} \cdot \vec{\mathbf{V}}\bar{\bar{I}} + \mu(\bar{\bar{D}} + \bar{\bar{D}}^T) \quad (2.17)$$

where  $\lambda$  is the dilational viscosity coefficient. This is related to the bulk viscosity by *Stokes hypothesis*:

$$\lambda = -\frac{2}{3}\mu \quad (2.18)$$

To find the contribution of the stress to the total forces acting on the control volume, the shear force must be integrated over the surface of the volume:

$$d\vec{\mathbf{F}}_\tau = \bar{\bar{\tau}} \cdot d\vec{\mathbf{S}} \quad (2.19)$$

The total force acting on the fluid within the control volume is therefore given by:

$$\vec{\mathbf{F}} = \iiint_R \rho \vec{\mathbf{f}}_g dR + \iint_S \bar{\vec{\tau}} \cdot \vec{\mathbf{dS}} \quad (2.20)$$

where  $\vec{f}_g$  is the externally applied force per unit mass.

The momentum flux through  $\mathbf{R}$  is given by:

$$\iint_S \vec{\mathbf{V}} (\rho \vec{\mathbf{V}} \cdot \vec{\mathbf{dS}}) \quad (2.21)$$

The mathematical expression for the momentum equation may now be written as

$$\iiint_R \frac{\partial}{\partial t} (\rho \vec{\mathbf{V}}) dR = \iiint_R \rho \vec{\mathbf{f}}_g dR + \iint_S \bar{\vec{\tau}} \cdot d\vec{\mathbf{S}} + \iint_S \vec{\mathbf{V}} (\rho \vec{\mathbf{V}} \cdot \vec{\mathbf{dS}}) \quad (2.22)$$

Again, using the divergence theorem to convert surface integrals to volume integrals, we get this:

$$\iiint_R \frac{\partial}{\partial t} (\rho \vec{\mathbf{V}}) dR = \iiint_R \{ \rho \vec{\mathbf{f}}_g + \vec{\nabla} \cdot \bar{\vec{\tau}} - \vec{\mathbf{V}} (\vec{\nabla} \cdot \rho \vec{\mathbf{V}}) + \rho (\vec{\mathbf{V}} \cdot \vec{\nabla}) \vec{\mathbf{V}} \} dR \quad (2.23)$$

As with the continuity equation, this leads to this final equation:

$$\frac{\partial}{\partial t} (\rho \vec{\mathbf{V}}) - \rho \vec{\mathbf{f}}_g - \vec{\nabla} \cdot \bar{\vec{\tau}} + \vec{\mathbf{V}} (\vec{\nabla} \cdot \rho \vec{\mathbf{V}}) + \rho (\vec{\mathbf{V}} \cdot \vec{\nabla}) \vec{\mathbf{V}} = 0 \quad (2.24)$$

### 2.3 Energy Equation

The energy equation follows from the principle of conservation of energy.

The net rate of increase of the internal and kinetic energy, per unit mass, in  $\mathbf{R}$  is equal to the net flux of heat into  $\mathbf{R}$  through the surface  $\mathbf{S}$  due to heat conduction, plus the net rate of work done on  $\mathbf{R}$  due to body and surface forces, plus the net influx of energy into  $\mathbf{R}$  through  $\mathbf{S}$  due to the fluid motion.

It must be assumed that the classical laws of thermodynamics, including the first law, hold in the presence of shear stress and heat conduction in order for the statement to be valid. if  $\mathbf{e}$  is the internal energy of the fluid per unit mass, the net increase of the internal and kinetic energy is given by:

$$\iiint_R \left\{ \rho e + \rho \frac{V^2}{2} \right\} dR \quad (2.25)$$

The net flux of heat into  $\mathbf{R}$  may be found by integrating the inward component of the heat flux vector  $\vec{\mathbf{Q}}$  over the surface:

$$\iint_S \vec{\mathbf{Q}} \cdot d\vec{\mathbf{S}} \quad (2.26)$$

The work done on the fluid is a function of both body forces and shearing forces, and is given by

$$\iint_S \vec{\mathbf{V}} \cdot (\vec{\tau} \cdot d\vec{\mathbf{S}}) + \iiint_R (\rho \vec{\mathbf{f}}_{\mathbf{g}} \cdot \vec{\mathbf{V}}) dR \quad (2.27)$$

Finally, the net influx of energy due to the fluid motion is given by:

$$\iint_S \left( \rho \vec{\mathbf{V}} \cdot d\vec{\mathbf{S}} \right) \left( e + \frac{V^2}{2} \right) \quad (2.28)$$

Combining these results, the energy equation becomes:



$$\begin{aligned}
\iiint_R \frac{\partial}{\partial t} \left\{ \rho \left( e + \frac{v^2}{2} \right) \right\} dR = & \\
& - \iint_S \vec{\mathbf{Q}} \cdot d\vec{\mathbf{S}} \\
& + \iiint_R \rho \vec{\mathbf{f}}_{\mathbf{g}} \cdot \vec{\mathbf{V}} dR \\
& + \iint_S \vec{\mathbf{V}} \cdot \left( \vec{\bar{\tau}} \cdot d\vec{\mathbf{S}} \right) \\
& - \iint_S \left( \rho \vec{\mathbf{V}} \cdot d\vec{\mathbf{S}} \right) \left( e + \frac{V^2}{2} \right) = 0
\end{aligned} \tag{2.29}$$

Which leads to this final result:

$$\begin{aligned}
\frac{\partial}{\partial t} \rho \left( e + \frac{V^2}{2} \right) & \\
& + \vec{\nabla} \cdot \vec{\mathbf{Q}} \\
& - \rho \vec{\mathbf{f}}_{\mathbf{g}} \cdot \vec{\mathbf{V}} \\
& - \vec{\nabla} \cdot \left( \vec{\bar{\tau}} \cdot \vec{\mathbf{V}} \right) \\
& - \rho \vec{\mathbf{V}} \cdot \vec{\nabla} \left( e + \frac{V^2}{2} \right) = 0
\end{aligned} \tag{2.30}$$

If the working fluid is assumed to be Newtonian, the heat flux is a function of thermodynamic state only and may be given as:

$$\vec{\mathbf{Q}} = -k \vec{\nabla} T \tag{2.31}$$

where  $k$  is the thermal conductivity of the fluid.

## 2.4 State Equations

The remaining equations needed to complete the set are the constitutive relationships for the working fluid. In this investigation the fluid is a perfect gas and obeys the thermal state equation:

$$P = \rho RT \quad (2.32)$$

where  $R$  is the ideal gas constant. If  $c_p$  is the specific heat at constant pressure, and  $c_v$  is the specific heat at constant volume, and if  $\gamma = \frac{c_p}{c_v}$  are given, then the caloric state equation is

$$e = c_v T \quad (2.33)$$

The definition of the static enthalpy may be given by:

$$h = c_p T = e + \frac{P}{\rho} \quad (2.34)$$

Recalling the definition of the substantive derivative:

$$\frac{Df}{Dt} = \frac{\partial f}{\partial t} + \vec{V} \cdot \vec{\nabla} f \quad (2.35)$$

## 2.5 Summary

The complete system of equations necessary to describe the flow of a fluid may be summarized:

1.  $\frac{D\rho}{Dt} + \rho \vec{\nabla} \cdot \vec{V} = 0$
2.  $\rho \frac{D\vec{V}}{Dt} = \rho \vec{f}_g + \vec{\nabla} \cdot \bar{\bar{\tau}}$
3.  $\rho \frac{D}{Dt} \left( e + \frac{V^2}{2} \right) = \rho \vec{f}_g \cdot \vec{V} - \vec{\nabla} \cdot \vec{Q} + \vec{\nabla} \cdot (\bar{\bar{\tau}} \cdot \vec{V})$
4.  $P = \rho RT$
5.  $e = c_v T$
6.  $h = c_p T$
7.  $\gamma = \frac{c_p}{c_v}$
8.  $\bar{\bar{\tau}} = -P \vec{I} + \lambda (\vec{\nabla} \cdot \vec{V}) \vec{I} + \mu \{ (\vec{\nabla} \vec{V}) + (\vec{\nabla} \vec{V})^T \}$
9.  $\vec{Q} = -k \vec{\nabla} T$

10.  $\mu = \mu(T)$
11.  $\lambda = -\frac{2}{3}\mu$
12.  $k = k(T)$

### 3 Derivation of the Cylindrical Navier Stokes Equations

In this section the system of governing equations given previously will be expanded in a cylindrical coordinate system.

For cylindrical  $(x, r, \phi)$  coordinates, the velocity vector  $\vec{V}$  is given by:

$$\vec{V} = u\hat{e}_x + v\hat{e}_r + w\hat{e}_\phi \quad (3.1)$$

where  $\hat{e}_x$ ,  $\hat{e}_r$ , and  $\hat{e}_\phi$  are the unit vectors.

The grad  $\vec{\nabla}$  operator may be given as:

$$\vec{\nabla} = \hat{e}_x \frac{\partial}{\partial x} + \hat{e}_r \frac{\partial}{\partial r} + \frac{\hat{e}_\phi}{r} \frac{\partial}{\partial \phi} \quad (3.2)$$

Since the analysis that follows will require taking derivatives of the unit vectors, these expressions will be derived next.

The position vector  $\vec{r}$  may be written in cartesian coordinates as:

$$\begin{aligned} \vec{r} &= x\hat{i} + y\hat{j} + z\hat{k} \\ &= x\hat{i} + r \cos \phi \hat{j} + r \sin \phi \hat{k} \end{aligned} \quad (3.3)$$

Now the equations for the unit vectors are:

$$\hat{e}_x = \frac{\partial \vec{r}}{\partial x} = \hat{i} \quad (3.4)$$

$$\hat{e}_r = \frac{\partial \vec{r}}{\partial r} = \cos \phi \hat{j} + \sin \phi \hat{k} \quad (3.5)$$

$$\hat{e}_\phi = \frac{\partial \vec{r}}{\partial \phi} = -\sin \phi \hat{j} + \cos \phi \hat{k} \quad (3.6)$$

From these equations, the derivatives of the unit vectors can be found:

$$\frac{\partial \hat{e}_x}{\partial x} = \frac{\partial \hat{e}_x}{\partial r} = \frac{\partial \hat{e}_x}{\partial \phi} = 0 \quad (3.7)$$

$$\frac{\partial \hat{e}_r}{\partial x} = \frac{\partial \hat{e}_r}{\partial r} = 0 \quad (3.8)$$

$$\frac{\partial \hat{e}_r}{\partial \phi} = -\sin \phi \hat{j} + \cos \phi \hat{k} = \hat{e}_\phi \quad (3.9)$$

$$\frac{\partial \hat{e}_\phi}{\partial x} = \frac{\partial \hat{e}_\phi}{\partial r} = 0 \quad (3.10)$$

$$\frac{\partial \hat{e}_\phi}{\partial \phi} = -\cos \phi \hat{j} - \sin \phi \hat{k} = -\hat{e}_r \quad (3.11)$$

Using these expressions, the derivatives of a general vector function become:

$$\begin{aligned} \vec{F} &= F_1 \hat{e}_x + F_2 \hat{e}_r + F_3 \hat{e}_\phi \\ \frac{\partial \vec{F}}{\partial x} &= \frac{\partial F_1}{\partial x} \hat{e}_x + \frac{\partial F_2}{\partial x} \hat{e}_r + \frac{\partial F_3}{\partial x} \hat{e}_\phi \\ \frac{\partial \vec{F}}{\partial r} &= \frac{\partial F_1}{\partial r} \hat{e}_x + \frac{\partial F_2}{\partial r} \hat{e}_r + \frac{\partial F_3}{\partial r} \hat{e}_\phi \\ \frac{\partial \vec{F}}{\partial \phi} &= \frac{\partial F_1}{\partial \phi} \hat{e}_x + \left( \frac{\partial F_2}{\partial \phi} - F_3 \right) \hat{e}_r + \left( \frac{\partial F_3}{\partial \phi} + F_2 \right) \hat{e}_\phi \end{aligned} \quad (3.12)$$

where  $F_1$ ,  $F_2$ , and  $F_3$  are the vector components.

### 3.1 Continuity Equation

The continuity equation will be expanded first:

$$\frac{D\rho}{Dt} + \rho \vec{\nabla} \cdot \vec{V} = 0 \quad (3.13)$$

$$\frac{\partial \rho}{\partial t} + (\vec{V} \cdot \vec{\nabla} \rho) + \rho (\vec{\nabla} \cdot \vec{V}) = 0 \quad (3.14)$$

$$\frac{\partial \rho}{\partial t} + u \frac{\partial \rho}{\partial x} + v \frac{\partial \rho}{\partial r} + \frac{w}{r} \frac{\partial \rho}{\partial \phi} + \rho \left( \frac{\partial u}{\partial x} + \frac{\partial v}{\partial r} + \frac{1}{r} \frac{\partial w}{\partial \phi} + \frac{v}{r} \right) = 0 \quad (3.15)$$

After rearranging and combining terms, we get this form:

$$\frac{\partial \rho}{\partial t} + \frac{\partial}{\partial x} (\rho u) + \frac{1}{r} \frac{\partial}{\partial r} (\rho v r) + \frac{1}{r} \frac{\partial}{\partial \phi} (\rho w) = 0 \quad (3.16)$$

### 3.2 Momentum Equation

Before expanding the momentum equation, it will be convenient to use the following for the shear stress matrix:

$$\vec{\tau} = \vec{\tau}_1 \hat{e}_x + \vec{\tau}_2 \hat{e}_r + \vec{\tau}_3 \hat{e}_\phi \quad (3.17)$$

Where:

$$\begin{aligned} \vec{\tau}_1 &= \tau_{xx} \hat{e}_x + \tau_{xr} \hat{e}_r + \tau_{x\phi} \hat{e}_\phi \\ \vec{\tau}_2 &= \tau_{rx} \hat{e}_x + \tau_{rr} \hat{e}_r + \tau_{r\phi} \hat{e}_\phi \\ \vec{\tau}_3 &= \tau_{\phi x} \hat{e}_x + \tau_{\phi r} \hat{e}_r + \tau_{\phi\phi} \hat{e}_\phi \end{aligned} \quad (3.18)$$

In this investigation, body forces will be neglected. The momentum equation becomes:

$$\begin{aligned} \rho \frac{D\vec{V}}{Dt} &= \vec{\nabla} \cdot \vec{\tau} \\ \rho \left\{ \frac{\partial \vec{V}}{\partial t} + \vec{V} \cdot \vec{\nabla} \vec{V} \right\} &= \vec{\nabla} \cdot \vec{\tau} \end{aligned} \quad (3.19)$$

or

$$\begin{aligned}
\rho \left\{ \frac{\partial u}{\partial t} \hat{e}_x + \frac{\partial v}{\partial t} \hat{e}_r + \frac{\partial w}{\partial t} \hat{e}_\phi + u \frac{\partial \vec{V}}{\partial t} \hat{e}_x + v \frac{\partial \vec{V}}{\partial r} \hat{e}_r + \frac{w}{r} \frac{\partial \vec{V}}{\partial \phi} \hat{e}_\phi \right\} \\
= \hat{e}_x \cdot \frac{\partial}{\partial x} \{ \vec{\tau}_1 \hat{e}_x + \vec{\tau}_2 \hat{e}_r + \vec{\tau}_3 \hat{e}_\phi \} \\
+ \hat{e}_r \cdot \frac{\partial}{\partial r} \{ \vec{\tau}_1 \hat{e}_x + \vec{\tau}_2 \hat{e}_r + \vec{\tau}_3 \hat{e}_\phi \} \\
+ \frac{\hat{e}_\phi}{r} \cdot \frac{\partial}{\partial \phi} \{ \vec{\tau}_1 \hat{e}_x + \vec{\tau}_2 \hat{e}_r + \vec{\tau}_3 \hat{e}_\phi \} \\
= \frac{\partial \vec{\tau}_1}{\partial x} + \frac{\partial \vec{\tau}_2}{\partial r} + \frac{1}{r} \left\{ \frac{\partial \vec{\tau}_3}{\partial \phi} + \vec{\tau}_2 \right\}
\end{aligned} \tag{3.20}$$

By expanding this last expression and rearranging terms, the following form results for the momentum equation

$$\begin{aligned}
\rho \left\{ \frac{\partial u}{\partial t} \hat{e}_x + \frac{\partial v}{\partial t} \hat{e}_r + \frac{\partial w}{\partial t} \hat{e}_\phi \right\} \\
+ \rho u \left\{ \frac{\partial u}{\partial x} \hat{e}_x + \frac{\partial v}{\partial x} \hat{e}_r + \frac{\partial w}{\partial x} \hat{e}_\phi \right\} \\
+ \rho v \left\{ \frac{\partial u}{\partial r} \hat{e}_x + \frac{\partial v}{\partial r} \hat{e}_r + \frac{\partial w}{\partial r} \hat{e}_\phi \right\} \\
+ \frac{\rho w}{r} \left\{ \frac{\partial u}{\partial \phi} \hat{e}_x + \left( \frac{\partial v}{\partial \phi} - w \right) \hat{e}_r + \left( \frac{\partial w}{\partial \phi} + v \right) \hat{e}_\phi \right\} \\
= \left\{ \tau_{xx} \hat{e}_x + \tau_{xr} \hat{e}_r + \tau_{x\phi} \hat{e}_\phi \right\} \\
+ \left\{ \tau_{xr} \hat{e}_x + \tau_{rr} \hat{e}_r + \tau_{r\phi} \hat{e}_\phi \right\} \\
+ \frac{1}{r} \left\{ \left( \frac{\partial \tau_{x\phi}}{\partial \phi} + \tau_{xr} \right) \hat{e}_x \right. \\
+ \left( \frac{\partial \tau_{r\phi}}{\partial \phi} - \tau_{x\phi} + \tau_{rr} \right) \hat{e}_r \\
+ \left. \left( \frac{\partial \tau_{\phi\phi}}{\partial \phi} + 2\tau_{r\phi} \right) \hat{e}_\phi \right\}
\end{aligned} \tag{3.21}$$

In order for this vector equation to be valid, the component equations must also be valid. Thus the momentum equation will be satisfied if the following three equations are true:

$$\rho \frac{\partial u}{\partial t} + \rho u \frac{\partial u}{\partial x} + \rho v \frac{\partial u}{\partial r} + \frac{\rho w}{r} \frac{\partial u}{\partial \phi} = \frac{\partial \tau_{xx}}{\partial x} + \frac{\partial \tau_{xr}}{\partial r} + \frac{1}{r} \left\{ \frac{\partial \tau_{x\phi}}{\partial \phi} + \tau_{\phi x} \right\} \quad (3.22)$$

$$\rho \frac{\partial v}{\partial t} + \rho u \frac{\partial v}{\partial x} + \rho v \frac{\partial v}{\partial r} + \frac{\rho w}{r} \left( \frac{\partial v}{\partial \phi} - w \right) = \frac{\partial \tau_{xr}}{\partial x} + \frac{\partial \tau_{rr}}{\partial r} + \frac{1}{r} \left\{ \frac{\partial \tau_{x\phi}}{\partial \phi} - \tau_{\phi\phi} + \tau_{rr} \right\} \quad (3.23)$$

$$\rho \frac{\partial w}{\partial t} + \rho u \frac{\partial w}{\partial x} + \rho v \frac{\partial w}{\partial r} + \frac{\rho w}{r} \left( \frac{\partial w}{\partial \phi} + v \right) = \frac{\partial \tau_{x\phi}}{\partial x} + \frac{\partial \tau_{r\phi}}{\partial r} + \frac{1}{r} \left\{ \frac{\partial \tau_{\phi\phi}}{\partial \phi} + 2\tau_{r\phi} \right\} \quad (3.24)$$

### 3.3 Energy Equation

The expansion of the energy equation follows:

$$\begin{aligned}
& \rho \frac{D}{Dt} \left( e + \frac{V^2}{2} \right) = \\
& -\vec{\nabla} \cdot \vec{\mathbf{Q}} + \vec{\nabla} \cdot \left( \vec{\bar{\tau}} \cdot \vec{\mathbf{V}} \right) \\
& \rho \left\{ \frac{\partial}{\partial t} \left( e + \frac{V^2}{2} \right) + \vec{\mathbf{V}} \cdot \vec{\nabla} \left( e + \frac{V^2}{2} \right) \right\} \\
& = \vec{\nabla} \cdot \left( k \vec{\nabla} T \right) + \vec{\nabla} \cdot \left( \vec{\bar{\tau}} \cdot \vec{\mathbf{V}} \right) \\
& \rho \frac{\partial}{\partial t} \left( e + \frac{V^2}{2} \right) + \rho u \frac{\partial}{\partial x} \left( e + \frac{V^2}{2} \right) + \rho v \frac{\partial}{\partial r} \left( e + \frac{V^2}{2} \right) + \frac{\rho w}{r} \frac{\partial}{\partial \phi} \left( e + \frac{V^2}{2} \right) \\
& = \frac{\partial}{\partial x} \left( k \frac{\partial T}{\partial x} \right) + \frac{\partial}{\partial r} \left( k \frac{\partial T}{\partial r} \right) + \frac{1}{r} \left\{ \frac{\partial}{\partial \phi} \left( \frac{1}{r} k \frac{\partial T}{\partial \phi} \right) + k \frac{\partial T}{\partial r} \right\} \\
& \quad + \frac{\partial}{\partial x} (u\tau_{xx} + v\tau_{xr} + w\tau_{x\phi}) + \frac{\partial}{\partial r} (u\tau_{xr} + v\tau_{rr} + w\tau_{r\phi}) \\
& \quad + \frac{1}{r} \left\{ \frac{\partial}{\partial \phi} (u\tau_{x\phi} + v\tau_{r\phi} + w\tau_{\phi\phi}) + (u\tau_{xr} + v\tau_{rr} + w\tau_{r\phi}) \right\} \\
& \hspace{25em} (3.25)
\end{aligned}$$

This form will be recast using the definition of total enthalpy:

$$H = h + \frac{V^2}{2} = e + \frac{P}{\rho} + \frac{V^2}{2} \quad (3.26)$$

thus:

$$e + \frac{V^2}{2} = H - \frac{P}{\rho} \quad (3.27)$$

and the energy equation becomes:



$$\begin{aligned}
& \rho \frac{\partial}{\partial t} \left( H - \frac{P}{\rho} \right) + \rho u \frac{\partial}{\partial x} \left( H - \frac{P}{\rho} \right) + \rho v \frac{\partial}{\partial r} \left( H - \frac{P}{\rho} \right) + \frac{\rho w}{r} \frac{\partial}{\partial \phi} \left( H - \frac{P}{\rho} \right) \\
&= \frac{\partial}{\partial x} \left( k \frac{\partial T}{\partial x} \right) + \frac{\partial}{\partial r} \left( k \frac{\partial T}{\partial r} \right) + \frac{1}{r} \left\{ \frac{\partial}{\partial \phi} \left( \frac{1}{r} k \frac{\partial T}{\partial \phi} \right) + k \frac{\partial T}{\partial r} \right\} \\
&\quad + \frac{\partial}{\partial x} (u\tau_{xx} + v\tau_{xr} + w\tau_{x\phi}) + \frac{\partial}{\partial r} (u\tau_{xr} + v\tau_{rr} + w\tau_{r\phi}) \\
&\quad + \frac{1}{r} \left\{ \frac{\partial}{\partial \phi} (u\tau_{x\phi} + v\tau_{r\phi} + w\tau_{\phi\phi}) + (u\tau_{xr} + v\tau_{rr} + w\tau_{r\phi}) \right\}
\end{aligned} \tag{3.28}$$

Finally, the expressions for the shear stress components should be derived:

$$\bar{\tau} = -P\vec{\mathbf{I}} + \lambda \left( \vec{\nabla} \cdot \vec{\mathbf{V}} \right) \vec{\mathbf{I}} + \mu \left\{ \left( \vec{\nabla} \vec{\mathbf{V}} \right) + \left( \vec{\nabla} \vec{\mathbf{V}} \right)^T \right\} \tag{3.29}$$

The  $\vec{\nabla} \vec{\mathbf{V}}$  matrix has the following form:

$$\vec{\nabla} \vec{\mathbf{V}} = \begin{bmatrix} \frac{\partial u}{\partial x} & \frac{\partial u}{\partial r} & \frac{1}{r} \frac{\partial u}{\partial \phi} \\ \frac{\partial v}{\partial x} & \frac{\partial v}{\partial r} & \frac{1}{r} \frac{\partial v}{\partial \phi} - \frac{w}{r} \\ \frac{\partial w}{\partial x} & \frac{\partial w}{\partial r} & \frac{1}{r} \frac{\partial w}{\partial \phi} + \frac{v}{r} \end{bmatrix} \tag{3.30}$$

Thus, the shear stress components are:

$$\begin{aligned}
\tau_{xx} &= -P + \lambda \left\{ \frac{\partial u}{\partial x} + \frac{\partial v}{\partial r} + \frac{1}{r} \frac{\partial w}{\partial \phi} + \frac{v}{r} \right\} \\
\tau_{rr} &= -P + \lambda \left\{ \frac{\partial u}{\partial x} + \frac{\partial v}{\partial r} + \frac{1}{r} \frac{\partial w}{\partial \phi} + \frac{v}{r} + 2\mu \frac{\partial v}{\partial r} \right\} \\
\tau_{\phi\phi} &= -P + \lambda \left\{ \frac{\partial u}{\partial x} + \frac{\partial v}{\partial r} + \frac{1}{r} \frac{\partial w}{\partial \phi} + \frac{v}{r} + \frac{2\mu}{r} \frac{\partial w}{\partial \phi} + \frac{2v}{r} \right\} \\
\tau_{xr} &= \mu \left\{ \frac{\partial u}{\partial x} + \frac{\partial v}{\partial r} \right\} \\
\tau_{x\phi} &= \mu \left\{ \frac{\partial w}{\partial x} + \frac{1}{r} \frac{\partial u}{\partial \phi} \right\} \\
\tau_{r\phi} &= \mu \left\{ \frac{\partial w}{\partial r} + \frac{1}{r} \frac{\partial v}{\partial \phi} - \frac{w}{r} \right\}
\end{aligned} \tag{3.31}$$

## 4 Non-Dimensionalization

The Navier-Stokes equations presented in this report consist of a system of nine equations in as many unknowns. These unknowns and their dimensional units are summarized below:

Quantity	Symbol	English Units	Metric Units
Density	$\rho$	$slugs/ft^3$	$kg/m^3$
Pressure	$P$	$lbf/ft^2$	$N/m^2$
Temperature	$T$	$^{\circ}R$	$^{\circ}K$
Total Enthalpy	$H$	$ft^2/sec^2$	$m^2/sec^2$
x Velocity	$u$	$ft/sec$	$m/sec$
r Velocity	$v$	$ft/sec$	$m/sec$
$\phi$ Velocity	$w$	$ft/sec$	$m/sec$
Thermal Conductivity	$k$	$lbf/sec^{\circ}R$	$N/sec^{\circ}K$
Viscosity	$\nu$	$lbf\,sec/ft^2$	$N\,sec/m^2$

where

$$\begin{aligned} slug &= [lb\,sec^2/ft] \\ N &= [kg\,m/sec^2] \end{aligned} \quad (4.1)$$

The conversion factors needed to from one dimensional system to the other are

$$\begin{aligned} 1\,ft &= 0.3048\,meter \\ 1\,lbf &= 4.4482216152605\,Newton \\ 1^{\circ}R &= \frac{9^{\circ}}{5}\,K \end{aligned} \quad (4.2)$$

The dimensional properties above will non-dimensionalized by means of as yet unspecified quantities. For the present, a \* superscript will be used to denote a dimensional quantity. The non-dimensional quantities will be defined as follows:

$$\begin{aligned} P &= p^*/P_{ref}^* & T &= T^*/T_{ref}^* & \rho &= \rho^*/\rho_{ref}^* \\ u &= u^*/u_{ref}^* & v &= v^*/v_{ref}^* & w &= w^*/w_{ref}^* \\ \mu &= \mu^*/\mu_{ref}^* & k &= k^*/k_{ref}^* & H &= h^*/h_{ref}^* \end{aligned}$$

In addition to these definitions, the length scales will be nondimensionalized with some reference length.

$$l = l^*/l_{ref}^* \quad (4.3)$$

The particular choice of the nondimensionalizing reference quantities is by no means fixed and often depends on convention or tradition. However, in view of the fact that most numerical studies closely couple with experimental efforts for verification of results, it would appear appropriate to consider the quantities available to an experimental researcher in establishing test conditions.

A wind tunnel, unless it has a variable nozzle, will be designed to operate at a fixed Mach number. It will, therefore, operate at a fixed ratio of total to static property ratios. In general, the driving total pressure is variable and, in some cases, static temperature may be varied by using heaters, so these two test conditions, together with the test Mach number, will be readily available for any experimental study.

This information and the thermodynamic properties of the working fluid are sufficient to completely describe the test conditions. For the present numerical study, then, the following test conditions will be used to define the reference quantities:

Quantity	Units
$M_\infty$	-
$P_o^*$	$lb/ft^2$
$T^*$	$^{\circ}R$
$R_{gas}^*$	$ft^2/sec^2 \text{ } ^{\circ}R$
$c_p^*$	$ft/sec^2 \text{ } ^{\circ}R$
$c_v^*$	$ft^2/sec^2 \text{ } ^{\circ}R$

At this point, it would appear that the total quantities could be used for reference parameters. However, by using the perfect gas relations, the static quantities may be derived and used. Before making this decision, the governing equations should be nondimensionalized so that the groupings of reference quantities may be considered. Note that nondimensionalization of the length scale gives the following:

$$\frac{\partial}{\partial x} = l_{ref}^* \frac{\partial}{\partial x^*} \quad (4.4)$$

The angular derivatives will be left in their normal form. For the analysis that follows, the pressure component of the normal shear stress terms will

be removed. That is:

$$\tau_{xx} = \sigma_{xx} - \frac{\partial P}{\partial x} etc \quad (4.5)$$

Finally, since the present work will deal only with the steady form of the governing equations, the time derivatives will be eliminated . The nondimensionalization follows:

#### 4.1 Continuity

$$\frac{\rho_{ref}^* u_{ref}^*}{l_{ref}^*} \left\{ \frac{\partial}{\partial x} (\rho u) + \frac{1}{r} \frac{\partial}{\partial r} (\rho v r) + \frac{1}{r} \frac{\partial}{\partial \phi} (\rho w) \right\} = 0 \quad (4.6)$$

#### 4.2 x Momentum

$$\frac{\rho_{ref}^* u_{ref}^{*2}}{l_{ref}^*} \left\{ \rho u \frac{\partial u}{\partial x} + \rho v \frac{\partial u}{\partial r} + \frac{\rho w}{r} \frac{\partial u}{\partial \phi} \right\} \quad (4.7)$$

#### 4.3 r Momentum

$$\frac{\rho_{ref}^* u_{ref}^{*2}}{l_{ref}^*} \left\{ \rho u \frac{\partial v}{\partial x} + \rho v \frac{\partial v}{\partial r} + \frac{\rho w}{r} \left( \frac{\partial v}{\partial \phi} - w \right) \right\} \quad (4.8)$$

#### 4.4 $\phi$ Momentum

$$\frac{\rho_{ref}^* u_{ref}^{*2}}{l_{ref}^*} \left\{ \rho u \frac{\partial w}{\partial x} + \rho v \frac{\partial w}{\partial r} + \frac{\rho w}{r} \left( \frac{\partial w}{\partial \phi} + v \right) \right\} \quad (4.9)$$

### 5 Derivation of a Generalized Non-Orthogonal Coordinate Transformation

Solutions to the Navier-Stokes equations are not conveniently obtained in a coordinate system that is not tied closely to the body shape being considered. Therefore, an arbitrary body-oriented coordinate system will be used in this analysis, and the governing equations will be transformed into that system. Rather than considering the case where velocity vectors are everywhere tangent to the coordinate curves, though, the velocity vectors will be referenced to a conventional cylindrical coordinate system.

The generalized transformation will be given as:

$$(x, r, \phi) \Leftrightarrow (\xi, \eta, \delta) \quad (5.1)$$

Where:

$$\begin{aligned} \xi &= \xi(x) \\ \eta &= \eta(x, r, \phi) \\ \delta &= \delta(x, r, \phi) \end{aligned} \quad (5.2)$$

The cylindrical partial derivatives will now be:

$$\begin{aligned} \frac{\partial}{\partial x} &= \xi_x \frac{\partial}{\partial \xi} + \eta_x \frac{\partial}{\partial \eta} + \delta_x \frac{\partial}{\partial \delta} \\ \frac{\partial}{\partial r} &= \eta_r \frac{\partial}{\partial \eta} + \delta_r \frac{\partial}{\partial \delta} \\ \frac{\partial}{\partial \phi} &= \eta_\phi \frac{\partial}{\partial \eta} + \delta_\phi \frac{\partial}{\partial \delta} \end{aligned} \quad (5.3)$$

With similar equations for the higher derivatives.

The inverse transformation is given by:

$$\begin{aligned} x &= x(\xi) \\ r &= r(\xi, \eta, \delta) \\ \phi &= \phi(\xi, \eta, \delta) \end{aligned} \quad (5.4)$$

In order for this transformation to exist and be unique, the *Jacobian*  $\mathbf{J}$  must be everywhere nonzero. The *Jacobian* is defined as:

$$J = \begin{vmatrix} x_\xi & r_\xi & \phi_\xi \\ x_\eta & r_\eta & \phi_\eta \\ x_\delta & r_\delta & \phi_\delta \end{vmatrix} \quad (5.5)$$

For the transformations we are considering,  $x_\eta = x_\delta = 0$ . Thus the *Jacobian* becomes just:

$$J = x_\xi (r_\eta \phi_\delta - r_\delta \phi_\eta) \neq 0 \quad (5.6)$$

Total derivatives in both coordinate systems may be written as:

$$\begin{aligned}
dx &= x_\xi d\xi \\
dr &= r_\xi d\xi + r_\eta d\eta + r_\delta d\delta \\
d\phi &= \phi_\xi d\xi + \phi_\eta d\eta + \phi_\delta d\delta \\
d\xi &= \xi_x dx \\
d\eta &= \eta_x dx + \eta_r dr + \eta_\phi d\phi \\
d\delta &= \delta_x dx + \delta_r dr + \delta_\phi d\phi
\end{aligned} \tag{5.7}$$

Combining these equations and rearranging gives this:

$$\begin{aligned}
dx &= x_\xi \{\xi_x d\xi\} \\
dr &= r_\xi \{\xi_x d\xi\} + r_\eta \{\eta_x dx + \eta_r dr + \eta_\phi d\phi\} + r_\delta \{\delta_x dx + \delta_r dr + \delta_\phi d\phi\} \\
d\phi &= \phi_\xi \{\xi_x d\xi\} + \phi_\eta \{\eta_x dx + \eta_r dr + \eta_\phi d\phi\} + \phi_\delta \{\delta_x dx + \delta_r dr + \delta_\phi d\phi\}
\end{aligned} \tag{5.8}$$

Now, rearranging these equations and equating coefficients, the following equations result:

$$x_\xi \xi_x = 1 \tag{5.9}$$

$$r_\xi \xi_x + r_\eta \eta_x + r_\delta \delta_x = 0 \tag{5.10}$$

$$r_\eta \eta_r + r_\delta \delta_r = 1 \tag{5.11}$$

$$r_\eta \eta_\phi + r_\delta \delta_\phi = 0 \tag{5.12}$$

$$\phi_\xi \xi_x + \phi_\eta \eta_x + \phi_\delta \delta_x = 0 \tag{5.13}$$

$$\phi_\eta \eta_r + \phi_\delta \delta_r = 0 \tag{5.14}$$

$$\phi_\eta \eta_\phi + \phi_\delta \delta_\phi = 1 \tag{5.15}$$

From this system of equations, the transformation coefficients needed to express partial derivatives in that system, that is all partial derivatives will be taken in the transformed coordinate system. Performing this analysis, the results are:

$$\begin{aligned}
\xi_x &= 1/\xi_x \\
\eta_x &= \{r_\xi \phi_\xi - r_\xi \phi_\delta\}/J \\
\delta_x &= \{\phi_\eta r_\xi - r_\eta \phi_\xi\}/J \\
\eta_r &= \{\phi_\delta x_\xi\}/J \\
\delta_r &= -\{\phi_\eta x_\xi\}/J \\
\eta_\phi &= -\{r_\delta x_\xi\}/J \\
\delta_\phi &= \{r_\eta x_\xi\}/J
\end{aligned} \tag{5.16}$$

If second derivatives must also be transformed, this may be accomplished by differentiating previous expressions:

$$\begin{aligned}
F_{xx} &= \xi_{xx} F_\xi + \eta_{xx} F_\eta + \delta_{xx} F_\delta + \\
&\quad \xi_x \{\xi_x F_{\xi\xi} + \eta_x F_{\xi\eta} + \delta_x F_{\xi\delta}\} + \\
&\quad \eta_x \{\xi_x F_{\xi\eta} + \eta_x F_{\eta\eta} + \delta_x F_{\eta\delta}\} + \\
&\quad \delta_x \{\xi_x F_{\xi\delta} + \eta_x F_{\eta\delta} + \delta_x F_{\delta\delta}\}
\end{aligned} \tag{5.17}$$

$$\begin{aligned}
F_{xr} &= \eta_{xr} F_\eta + \delta_{xr} F_\delta + \delta_{xr} F_\delta + \\
&\quad \xi \{\eta_r F_{\xi\eta} + \delta_r F_{\delta\delta}\} + \\
&\quad \eta_x \{\eta_r F_{\eta\eta} + \delta_r F_{\eta\delta}\} + \\
&\quad \delta_x \{\eta_r F_{\eta\delta} + \delta_r F_{\delta\delta}\}
\end{aligned} \tag{5.18}$$

$$\begin{aligned}
F_{x\phi} &= \eta_{x\phi} F_\eta + \delta_{x\phi} F_\delta + \\
&\quad \xi_x \{\eta_\phi F_{\xi\eta} + \eta_\phi F_{\xi\delta}\} + \\
&\quad \eta_x \{\eta_\phi F_{\eta\eta} + \delta_\phi F_{\eta\delta}\} + \\
&\quad \delta_x \{\eta_\phi F_{\eta\delta} + \delta_\phi F_{\delta\delta}\}
\end{aligned} \tag{5.19}$$

$$\begin{aligned}
F_{rr} = \eta_{rr} + \delta_{rr}F_{\delta} + \\
\eta_r\{\eta_r F_{\eta\eta} + \delta_r F_{\eta\delta}\} + \\
\delta_r\{\eta_r F_{\eta\delta} + \delta_r F_{\delta\delta}\} \quad (5.20)
\end{aligned}$$

$$\begin{aligned}
F_{r\phi} = \eta_{r\phi}F_{\eta} + \delta_{r\phi}F_{\delta} + \\
\eta_r\{\eta_{\phi}F_{\eta\eta} + \delta_{\phi}F_{\eta\delta}\} + \\
\delta_r\{\eta_{\phi}F_{\eta\delta} + \delta_{\phi}F_{\delta\delta}\} \quad (5.21)
\end{aligned}$$

$$\begin{aligned}
F_{\phi\phi} = \eta_{\phi\phi}F_{\eta} + \delta_{\phi\phi}F_{\delta} + \\
\eta_{\phi}\{\eta_{\phi}F_{\eta\eta} + \delta_{\phi}F_{\eta\delta}\} + \\
\delta_{\phi}\{\eta_{\phi}F_{\eta\delta} + \delta_{\phi}F_{\delta\delta}\} \quad (5.22)
\end{aligned}$$

The new transformation coefficients may also be obtained by differentiating previous expressions. These will not be expanded fully here:

$$\begin{aligned}
\xi_{xx} &= -\xi_x x_{\xi\xi} / x_{\xi}^2 \\
\eta_{xx} &= \xi_x(\eta_x)_{\xi} + \eta_x(\eta_x)_{\eta} + \delta_x(\eta_x)_{\delta} \\
\eta_{xr} &= \eta_r(\eta_x)_{\eta} + \delta_r(\eta_x)_{\delta} \\
\eta_{x\phi} &= \eta_{\phi}(\eta_x)_{\eta} + \delta_{\phi}(\eta_x)_{\delta} \\
\eta_{rr} &= \eta_r(\eta_r)_{\eta} + \delta_r(\eta_r)_{\delta} \\
\eta_{r\phi} &= \eta_{\phi}(\eta_r)_{\eta} + \delta_{\phi}(\eta_r)_{\delta} \\
\eta_{\phi\phi} &= \eta_{\phi}(\eta_{\phi} h i)_{\eta} + \delta_{\phi}(\eta_{\phi})_{\delta} \\
\delta_{xx} &= \xi_x(\delta_x)_{\xi} + \eta_x(\delta_x)_{\eta} + \delta_x(\delta_x)_{\delta} \\
\delta_{xr} &= \eta_r(\delta_x)_{\eta} + \delta_r(\delta_x)_{\delta} \\
\delta_{x\phi} &= \eta_{\phi}(\delta_x)_{\eta} + \delta_{\phi}(\delta_x)_{\delta} \\
\delta_{rr} &= \eta_r(\delta_r)_{\eta} + \delta_r(\delta_r)_{\delta} \\
\delta_{r\phi} &= \eta_{\phi}(\delta_r)_{\eta} + \delta_{\phi}(\delta_r)_{\delta} \\
\delta_{\phi\phi} &= \eta_{\phi}(\delta_{\phi})_{\eta} + \delta_{\phi}(\delta_{\phi})_{\delta}
\end{aligned} \quad (5.23)$$



Note that at this point nothing has been said about the actual relationship between points in the two coordinate systems except that the *Jacobian* be nonzero. In fact, any relationship that maps points uniquely from one system to the other may be used. If the error associated with obtaining the transformation coefficients numerically is acceptable, then the functional relationship between the two systems may remain unknown. In this manner any method of obtaining the point to point mapping may be used and not just the methods with a firm analytical foundation. This is the approach that will be taken here since it does not restrict the range of possible mapping methods to any particular class

## 6 Analytic Coordinate System for the Ogive-Cylinder at Angle of Attack

Since the generalized three-dimensional code to be developed will be numerically evaluating the transformation coefficients, it will be useful to solve a simple problem using both analytic and numerically evaluated coefficients. For this analysis, a coordinate system will be described for use in solving flow fields about an ogive-cylinder at angle of attack.

To simplify the analysis, the coordinate system will be a modified cylindrical system centered on the body axis. At any axial station, the computational domain will extend from the body outward to a specified outer limit. The outer boundary will be a circle with its center shifted off of the body axis to allow the bow shock to be more nearly aligned with this boundary.

The outer boundary radius and offset point location will vary linearly with  $x$ . The details of this system are shown in the following figures.

The transformation will be describes as follows:

$$\begin{aligned}\xi &= \xi(x) \\ \eta &= \eta(x, r, \phi) \\ \delta &= \delta(\phi)\end{aligned}\tag{6.1}$$

It will be desirable to allow the step size to vary away from the body in order to compress points in the boundary layer near the body for the present. This variation will be defined as some function of the fractional distance between the body and outer boundary. In this case ,  $\eta$  will be defined as:

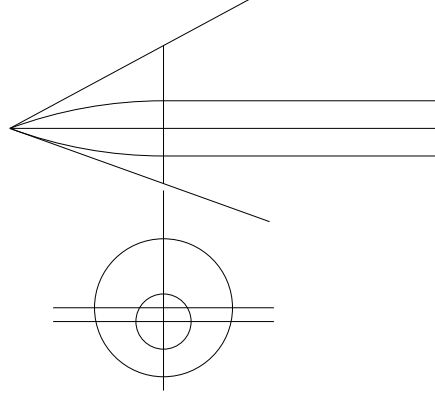


Figure 2: Ogive-cylinder Grid

$$\begin{aligned}\eta &= \eta(\bar{r}) \\ \bar{r} &= (r - r_b)/(r_s - r_b)\end{aligned}\tag{6.2}$$

The required transformation functions are:

$$\begin{aligned}F_x &= \xi/x F_\xi + \eta_x F_\eta \\ F_r &= \eta_r F_\eta \\ F_\phi &= \eta_\phi F_\eta + \delta_\phi F_\delta\end{aligned}\tag{6.3}$$

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## References

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