(1) Calculate equilibrium solution with regards to rigid body modes	$oldsymbol{\lambda}_{N0} = \mathbf{AG}(\mathbf{G}^T\mathbf{AG})^{-1}\mathbf{e}$
	$\mathbf{P} = \mathbf{I} - \mathbf{AG}(\mathbf{G}^T \mathbf{AG})^{-1} \mathbf{G}^T$
(3) Calculate residual(qap) in	1 - 1 43(3 43) 3
	$\mathbf{r}_0 = \mathbf{P}^T (\mathbf{d} - \mathbf{F} oldsymbol{\lambda}_0)$
(4) Preconditioning	$\overline{Z_0} = Sr_0$
(5) Rigid body-components of forces	$\mathbf{W}_0 = \mathbf{PZ}_0$
(6) Initialize	$\lambda_{F0} = 0, i = 0$
While not converged	$\sqrt{\mathbf{r}^T\mathbf{Z}1} > \epsilon$
(7) Compute gap-changes	
$due\ to\ forces\ {f W}_i$	${\sf Q}_i = {\sf FW}_i$
(8) Auxiliary parameter	$\mathbf{\Delta}_i = \mathbf{Q}_i{}^T \mathbf{W}_i$
(9) Auxiliary parameter	$oldsymbol{\gamma}_i = {f Z}_i{}^T{f r}_i$
(10) Auxiliary parameter	$oldsymbol{lpha}_i = oldsymbol{\Delta}_i^{\ +} oldsymbol{\gamma}_i$
(11) Step in new direction	$oldsymbol{\lambda_{F}}_{i+1} = oldsymbol{\lambda_{F}}_i + oldsymbol{W}_i oldsymbol{lpha}_i$
(12) Gap change due to force step	$\mathbf{r}_{i+1} = \mathbf{r}_i - \mathbf{P}^T \mathbf{Q}_i oldsymbol{lpha}_i$
(13) New	$\mathbf{Z}_{i+1} = Sr_{i+1}$
Loop over all substructures	$for \ s = 1,, N \ do$
(14) Compute convergence indice	$t_i^s = rac{\langle W_i oldsymbol{lpha}_i, F^{[s]} W_i oldsymbol{lpha}_i angle}{r_{i+1}^{\ T} S^{[s]} r_{i+1}}$
$(15) \tau - test$	$t_i^s < \tau$?
true	false
(16) Add direction to search space $\mathbf{Z}_{i+1} = [Z_{i+1} \mathbf{S}^{[s]}\mathbf{r}]$	(17) Do nothing
(18) Remove rigid body-components of forces	$\mathbf{W}_{i+1} = \mathbf{PZ}_{i+1}$
Loop over previous iterations	for: $0 \le j \le i$
(19) Compute orthogonalization	factor $oldsymbol{\phi}_{i,j} = oldsymbol{Q}_j^T oldsymbol{W}_{i+1}$
(20) Orthogonalize to direction j	$\mathbf{W}_{i+1} \leftarrow \mathbf{W}_{i+1} - \mathbf{W}_{j} \mathbf{\Delta}_{j}^{\ +} \mathbf{\phi}_{i,j}$
(21) Increase iteration counter	$i \leftarrow i + 1$
(22) Compute total interface forces	$\lambda = \lambda_{N0} + \lambda_{F0}$