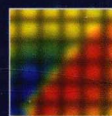


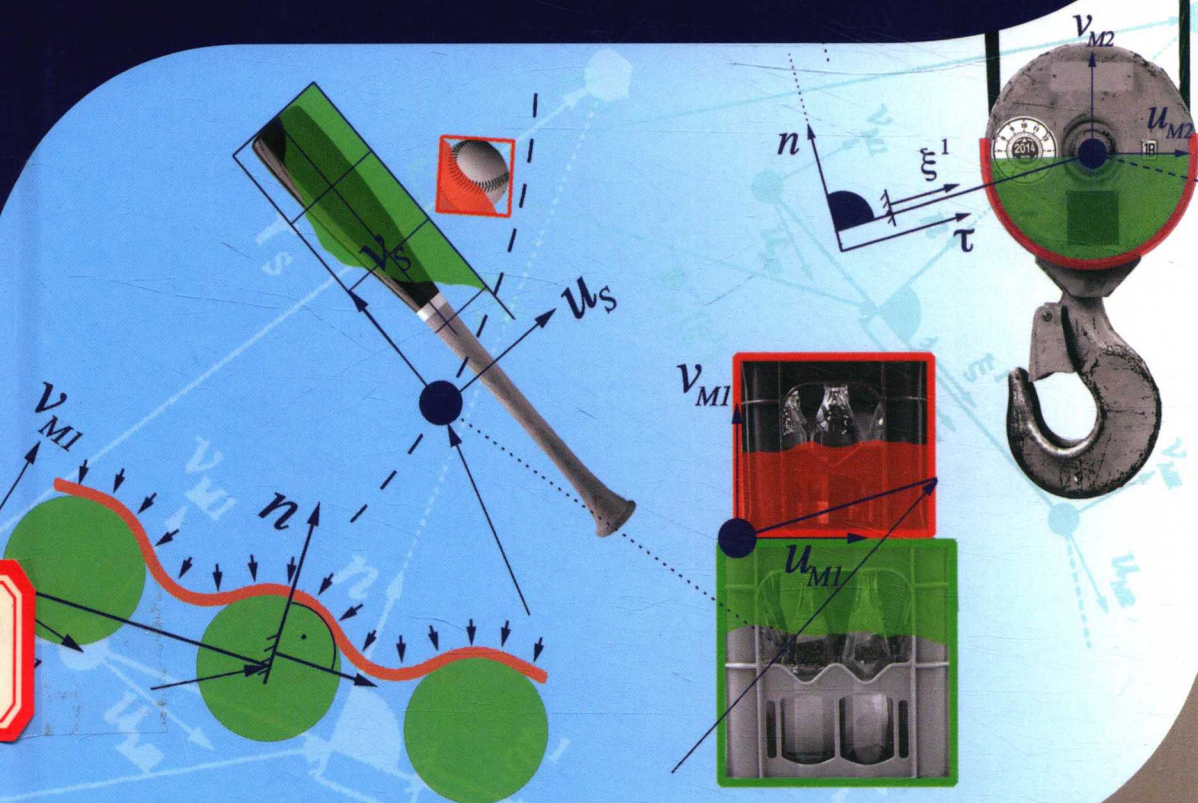
WILEY SERIES IN COMPUTATIONAL MECHANICS



# Introduction to Computational Contact Mechanics

A Geometrical Approach

Alexander Konyukhov and Ridvan Izi



WILEY

# **INTRODUCTION TO COMPUTATIONAL CONTACT MECHANICS**

## **A GEOMETRICAL APPROACH**

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# **INTRODUCTION TO COMPUTATIONAL CONTACT MECHANICS**

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# Series Preface

Since the publication of the seminal paper on contact mechanics by Heinrich Hertz in 1882, the field has grown into an important branch of mechanics, mainly due to the presence of a high number of applications in many branches of engineering. The advent of computational techniques to handle contact between deformable bodies has greatly enhanced the possibility of analyzing contact problems in detail, resulting, for instance, in an enhanced insight into wear problems. The numerical treatment of contact belongs to the hardest problems in computational engineering, and many publications and books have been written to date, marking progress in the field. An *Introduction to Computational Contact Mechanics: A Geometrical Approach* stands out in terms of the clear and geometric approach chosen by the authors. The book covers many aspects of computational contact mechanics and benefits from clear notation. It comes with detailed derivations and explanations, and an exhaustive number of programming and verification tasks, which will help the reader to master the subject.

# Preface

Computational contact mechanics within the last decade has developed into a separate branch of computational mechanics dealing exclusively with the numerical modeling of contact problems. Several monographs on computational contact mechanics summarize the study of computational algorithms used in the computational contact mechanics. The most famous, and subject to several editions, are the monographs by Wriggers (2002) and Laursen (2002). Most of the topics are explained at a high research level, which requires a very good knowledge of both numerical mathematics and continuum mechanics. Therefore, this book was the idea of Professor Dr. Ing. Schweizerhof back in 2006, who proposed to me to introduce a course in computational contact mechanics in such a manner that the prerequisite knowledge should be minimized. The main goal was to explain many algorithms used in well-known Finite Element Software packages (ANSYS, ABAQUS, LS-DYNA) in a simple manner and learn their finite element implementation. The starting point of the course was a reduction of the original 3D finite element algorithms into the 2D case and an introductory part to differential geometry. As field of the research has developed, the exploitation of the geometrical methods, the so-called covariant approach, after years of research has lead to the joint research monograph together with Professor Dr. Ing. Schweizerhof in Konyukhov and Schweizerhof (2012) *Computational Contact Mechanics: Geometrically Exact Theory for Arbitrary Shaped Bodies*. At this point, we would like to mention other monographs that we recommend for reading in computational contact mechanics Kikuchi (1988), Sofonea (2012), Yastrebov (2013), in friction and tribology Popov (2010) and also, the famous book on analytical methods in contact mechanics by Johnson (1987).

Ridvan Izi joined the computational contact mechanics course in 2009 and started to give assistance from 2011 to the exercise programming part, and made a lot of effort to make the exercises “easy going” for the students. Thus, the joint work started, leading to the current structure of the exercises in Part II. We were trying to keep this structure independent as much as possible from the programming language, although the course has been given in FEAP (Finite Element Analysis Program) written in FORTRAN.

The current book is based on the course being taught over several years at the Karlsruhe Institute of Technology and proved to be an effective guide for graduate and PhD students studying computational contact mechanics. The geometrically exact theory



for contact interaction is delivered in a simple attractive engineering manner available for undergraduate students starting from 1D geometry.

The book is subdivided into two parts:

- Part I contains the theoretical basis for the computational contact mechanics, including necessary material for lectures in computational contact mechanics.
- Part II includes the necessary material for the practical implementation of algorithms, including verification and numerical analysis of contact problems. Part II is consequently constructed following the theory considered in Part I.
- In addition, the original FORTRAN programs, including all numerical examples considered in Part II, are available from the supporting Wiley website at [www.wiley.com/go/Konyukhov](http://www.wiley.com/go/Konyukhov)

The basis of the geometrically exact theory for contact interaction is to build the proper coordinate system to describe the contact interaction in all its geometrical detail. This results in the special structure of the computational mechanics course – study in applied differential geometry, kinematics of contact, formulation of a weak form and linearization in a special coordinate system in a covariant form. Afterward, most popular methods to enforce contact conditions – the penalty method, Lagrange multipliers, augmented Lagrange multipliers, Mortar method and the more seldomly used Nitsche method – are formulated consequently, first for 1D and then for 2D systems finally leading to examples in 3D. It then applies to finite element discretization. The structure of contact elements for these methods is studied in detail and all numerical algorithms are derived in a form ready for implementation. Thus, the structure of contact elements is carefully derived for various situations: Node-To-Node (NTN), Node-To-Segment (NTS) and Segment-To-Segment (STS) contact approaches. Special attention is given to the derivation of contact elements with rigid bodies of simple geometry such as the Segment-To-Analytical Segment (STAS) approach.

Part II of the book contains programming schemes for the following finite elements: surface-to-analytical (rigid) surface, NTN for several methods: penalty, Lagrange, Nitsche methods; node-to-segment for both non-frictional and frictional cases, with Mortar type segment-to-segment and 3D node-to-segment contact elements. Through examples, special attention is given to the implementation of normal following forces, which is derived a particular case of implementation for the frictionless contact algorithm.

All examples are given in a sequential manner with increasing complexity, which allows the reader to program these elements easily. Though the course has been designed for the FEAP user using FORTRAN, the structure of all examples is given in a programming-block manner, which allows the user to program all elements using any, convenient programming language or just mathematical software such as MATLAB.



The examples and corresponding tests are conceptualized in order to study many numerical phenomena appearing in computational contact mechanics, such as influence of the penalty parameters, selection of meshes and element type for the contact patch test for non-frictional and frictional cases.

The original implementation of the derived contact elements was carried out in one of the earliest versions of FEAP originating from Professor Robert Taylor, University of California, Berkley. The Finite Element Analysis Program (FEAP) appeared at the Institute of Mechanics of the Karlsruhe Institute of Technology due to the joint collaboration between Robert Taylor and Karl Schweizerhof who further developed the FEAP code into FEAP-MeKa with the famous solid-shell finite element. The code used in the current course is a simplified student version without any finite elements used for research and is used for educational purposes. During private communications, Professor Taylor confirmed that a free updated version is available and is still supported at <http://www.ce.berkeley.edu/projects/feap/feappv/>. I am particularly thankful for his kind agreement to link the programming given in the current course to the updated version of FEAP. Though all originally implemented subroutines for contact elements are shown within the old version of FEAP (or FEAP-MeKa) together with all necessary specifications (geometry, loads, boundary conditions, etc.) of tasks, the subroutines can be easily rearranged for the updated version of FEAP. The code, together with numerical examples, is essential in order to work with examples given in Part II. Any reader familiar with FEAP can straightforwardly adopt this code to his/her needs. The code is written in FORTRAN, but the straightforward programming structure, without using any math library, is intentionally preserved in order that any user can easily adopt the code to any other programming language. Moreover, we do really hope that the flowcharts, provided for each contact element can be used for programming of computational contact mechanics exercises using symbolic mathematical software such as MATLAB, MATHEMATICA, and so on.

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# Acknowledgments

We are thankful to Professor Karl Schweizerhof for giving us the great opportunity to develop such a course for students.

We would like to thank Professor Robert Taylor for his kind agreement to link our course of computational contact mechanics to the current and updated version of FEAP, thus encouraging us to work with the current code. Professor Taylor confirmed that the free version is available and is still supported at <http://www.ce.berkeley.edu/projects/feap/feappv/>.

The group of excellent student assistants has been busy carefully testing all examples given in Part II in less than a year. We would particularly like to thank Christian Lorenz, Merita Haxhibeti, Isabelle Niesel and Oana Mrenes for careful testing of the contact mechanics examples and Marek Fassin for testing necessary structural finite elements. An additional thanks to Oana Mrenes for the many editing efforts made with contemporary LATEX packages.

Many thanks to Johann Bitzenbauer for the careful reading of the current manuscript version and his fruitful proposals that lead to improvement.

The book in its current version has been tested in a workshop for computational contact mechanics recently at the Bundeswehr Universität München – and we are thankful to Georgios Michaloudis for his careful reading and proposals.

The work on this book took us many weekends, sacrificing time spent with our families. At this last, but not least point, we would like to especially thank our families for their understanding and moral support during the work on this book.

# Contents

<b>Series Preface</b>	<b>xiii</b>
<b>Preface</b>	<b>xv</b>
<b>Acknowledgments</b>	<b>xix</b>
 <b>Part I THEORY</b>	
<b>1 Introduction with a Spring-Mass Frictionless Contact System</b>	<b>3</b>
1.1 Structural Part – Deflection of Spring-Mass System	3
1.2 Contact Part – Non-Penetration into Rigid Plane	4
1.3 Contact Formulations	5
1.3.1 <i>Lagrange Multiplier Method</i>	5
1.3.2 <i>Penalty Method</i>	6
1.3.3 <i>Augmented Lagrangian Method</i>	8
 <b>2 General Formulation of a Contact Problem</b>	<b>13</b>
2.1 Structural Part – Formulation of a Problem in Linear Elasticity	13
2.1.1 <i>Strong Formulation of Equilibrium</i>	14
2.1.2 <i>Weak Formulation of Equilibrium</i>	15
2.2 Formulation of the Contact Part (Signorini's problem)	17
 <b>3 Differential Geometry</b>	<b>23</b>
3.1 Curve and its Properties	23
3.1.1 <i>Example: Circle and its Properties</i>	26
3.2 Frenet Formulas in 2D	28
3.3 Description of Surfaces by Gauss Coordinates	29
3.3.1 <i>Tangent and Normal Vectors: Surface Coordinate System</i>	29
3.3.2 <i>Basis Vectors: Metric Tensor and its Applications</i>	30
3.3.3 <i>Relationships between Co- and Contravariant Basis Vectors</i>	33
3.3.4 <i>Co- and Contravariant Representation of a Vector on a Surface</i>	34
3.3.5 <i>Curvature Tensor and Structure of the Surface</i>	35

3.4	Differential Properties of Surfaces	37
3.4.1	<i>The Weingarten Formula</i>	37
3.4.2	<i>The Gauss–Codazzi Formula</i>	38
3.4.3	<i>Covariant Derivatives on the Surface</i>	38
3.4.4	<i>Example: Geometrical Analysis of a Cylindrical Surface</i>	39
<b>4</b>	<b>Geometry and Kinematics for an Arbitrary Two Body Contact Problem</b>	<b>45</b>
4.1	Local Coordinate System	46
4.2	Closest Point Projection (CPP) Procedure – Analysis	48
4.2.1	<i>Existence and Uniqueness of CPP Procedure</i>	49
4.2.2	<i>Numerical Solution of CPP Procedure in 2D</i>	54
4.2.3	<i>Numerical Solution of CPP Procedure in 3D</i>	54
4.3	Contact Kinematics	55
4.3.1	<i>2D Contact Kinematics using Natural Coordinates <math>s</math> and <math>\zeta</math></i>	58
4.3.2	<i>Contact Kinematics in 3D Coordinate System</i>	59
<b>5</b>	<b>Abstract Form of Formulations in Computational Mechanics</b>	<b>61</b>
5.1	Operator Necessary for the Abstract Formulation	61
5.1.1	<i>Examples of Operators in Mechanics</i>	61
5.1.2	<i>Examples of Various Problems</i>	62
5.2	Abstract Form of the Iterative Method	63
5.3	Fixed Point Theorem (Banach)	64
5.4	Newton Iterative Solution Method	65
5.4.1	<i>Geometrical Interpretation of the Newton Iterative Method</i>	66
5.5	Abstract Form for Contact Formulations	69
5.5.1	<i>Lagrange Multiplier Method in Operator Form</i>	69
5.5.2	<i>Penalty Method in Operator Form</i>	71
<b>6</b>	<b>Weak Formulation and Consistent Linearization</b>	<b>73</b>
6.1	Weak Formulation in the Local Coordinate System	73
6.2	Regularization with Penalty Method	75
6.3	Consistent Linearization	75
6.3.1	<i>Linearization of Normal Part</i>	76
6.4	Application to Lagrange Multipliers and to Following Forces	79
6.4.1	<i>Linearization for the Lagrange Multipliers Method</i>	80
6.4.2	<i>Linearization for Following Forces: Normal Force or Pressure</i>	80
6.5	Linearization of the Convective Variation $\delta\xi$	81
6.6	Nitsche Method	81
6.6.1	<i>Example: Independence of the Stabilization Parameter</i>	83

<b>7</b>	<b>Finite Element Discretization</b>	<b>85</b>
7.1	Computation of the Contact Integral for Various Contact Approaches	86
7.1.1	<i>Numerical Integration for the Node-To-Node (NTN)</i>	86
7.1.2	<i>Numerical Integration for the Node-To-Segment (NTS)</i>	86
7.1.3	<i>Numerical Integration for the Segment-To-Analytical Segment (STAS)</i>	86
7.1.4	<i>Numerical Integration for the Segment-To-Segment (STS)</i>	87
7.2	Node-To-Node (NTN) Contact Element	88
7.3	Nitsche Node-To-Node (NTN) Contact Element	89
7.4	Node-To-Segment (NTS) Contact Element	91
7.4.1	<i>Closest Point Projection Procedure for the Linear NTS Contact Element</i>	94
7.4.2	<i>Peculiarities in Computation of the Contact Integral</i>	95
7.4.3	<i>Residual and Tangent Matrix</i>	96
7.5	Segment-To-Analytical-Surface (STAS) Approach	98
7.5.1	<i>General Structure of CPP Procedure for STAS Contact Element</i>	98
7.5.2	<i>Closed form Solutions for Penetration in 2D</i>	100
7.5.3	<i>Discretization for STAS Contact Approach</i>	102
7.5.4	<i>Residual and Tangent Matrix</i>	102
7.6	Segment-To-Segment (STS) Mortar Approach	104
7.6.1	<i>Peculiarities of the CPP Procedure for the STS Contact Approach</i>	106
7.6.2	<i>Computation of the Residual and Tangent Matrix</i>	106
<b>8</b>	<b>Verification with Analytical Solutions</b>	<b>109</b>
8.1	Hertz Problem	109
8.1.1	<i>Contact Geometry</i>	110
8.1.2	<i>Contact Pressure and Displacement for Spheres: 3D Hertz Solution</i>	113
8.1.3	<i>Contact Pressure and Displacement for Cylinders: 2D Hertz Solution</i>	114
8.2	Rigid Flat Punch Problem	114
8.3	Impact on Moving Pendulum: Center of Percussion	116
8.4	Generalized Euler–Eytelwein Problem	118
8.4.1	<i>A Rope on a Circle and a Rope on an Ellipse</i>	119
<b>9</b>	<b>Frictional Contact Problems</b>	<b>121</b>
9.1	Measures of Contact Interactions – Sticking and Sliding Case: Friction Law	121
9.1.1	<i>Coulomb Friction Law</i>	123

9.2	Regularization of Tangential Force and Return Mapping Algorithm	123
9.2.1	<i>Elasto-Plastic Analogy: Principle of Maximum of Dissipation</i>	125
9.2.2	<i>Update of Sliding Displacements in the Case of Reversible Loading</i>	127
9.3	Weak Form and its Consistent Linearization	128
9.4	Frictional Node-To-Node (NTN) Contact Element	129
9.4.1	<i>Regularization of the Contact Conditions</i>	130
9.4.2	<i>Linearization the of Tangential Part for the NTN Contact Approach</i>	131
9.4.3	<i>Discretization of Frictional NTN</i>	131
9.4.4	<i>Algorithm for a Local Level Frictional NTN Contact Element</i>	133
9.5	Frictional Node-To-Segment (NTS) Contact Element	134
9.5.1	<i>Linearization and Discretization for the NTS Frictional Contact Element</i>	134
9.5.2	<i>Algorithm for a Local Level NTS Frictional Contact Element</i>	135
9.6	NTS Frictional Contact Element	135

## Part II PROGRAMMING AND VERIFICATION TASKS

<b>10</b>	<b>Introduction to Programming and Verification Tasks</b>	<b>139</b>
<b>11</b>	<b>Lesson 1 Nonlinear Structural Truss – elmt1.f</b>	<b>143</b>
11.1	Implementation	144
11.2	Examples	148
11.2.1	<i>Constitutive Laws of Material</i>	148
11.2.2	<i>Large Rotation</i>	149
11.2.3	<i>Snap-Through Buckling</i>	150
<b>12</b>	<b>Lesson 2 Nonlinear Structural Plane – elmt2.f</b>	<b>151</b>
12.1	Implementation	152
12.2	Examples	156
12.2.1	<i>Constitutive Law of Material</i>	156
12.2.2	<i>Large Rotation</i>	158
<b>13</b>	<b>Lesson 3 Penalty Node-To-Node (NTN) – elmt100.f</b>	<b>159</b>
13.1	Implementation	160
13.2	Examples	161
13.2.1	<i>Two Trusses</i>	161
13.2.2	<i>Three Trusses</i>	162
13.2.3	<i>Two Blocks</i>	163
<b>14</b>	<b>Lesson 4 Lagrange Multiplier Node-To-Node (NTN) – elmt101.f</b>	<b>165</b>
14.1	Implementation	166

14.2	Examples	168
14.2.1	<i>Two Trusses</i>	168
14.2.2	<i>Three Trusses</i>	169
<b>15</b>	<b>Lesson 5 Nitsche Node-To-Node (NTN) – <code>elmt102.f</code></b>	<b>171</b>
15.1	Implementation	171
15.2	Examples	174
15.2.1	<i>Two Trusses</i>	174
15.2.2	<i>Three Trusses</i>	174
<b>16</b>	<b>Lesson 6 Node-To-Segment (NTS) – <code>elmt103.f</code></b>	<b>177</b>
16.1	Implementation	178
16.2	Examples	181
16.2.1	<i>Two Blocks</i>	181
16.2.2	<i>Two Blocks – Horizontal Position</i>	182
16.2.3	<i>Two Cantilever Beams – Large Sliding Test</i>	183
16.2.4	<i>Hertz Problem</i>	183
16.3	Inverted Contact Algorithm – Following Force	185
16.3.1	<i>Verification of the Rotational Part – A Single Following Force</i>	186
<b>17</b>	<b>Lesson 7 Segment-To-Analytical-Segment (STAS) – <code>elmt104.f</code></b>	<b>189</b>
17.1	Implementation	190
17.2	Examples	193
17.2.1	<i>Block and Rigid Surface</i>	193
17.2.2	<i>Block and Inclined Rigid Surface</i>	194
17.2.3	<i>Block and Inclined Rigid Surface – different Boundary Condition</i>	195
17.2.4	<i>Bending Over a Rigid Cylinder</i>	196
17.3	Inverted Contact Algorithm – General Case of Following Forces	196
17.3.1	<i>Verification of a Rotational Part – A Single Following Force</i>	198
17.3.2	<i>Distributed Following Forces – Pressure</i>	199
17.3.3	<i>Inflating of a Bar</i>	201
<b>18</b>	<b>Lesson 8 Mortar/Segment-To-Segment (STS) – <code>elmt105.f</code></b>	<b>203</b>
18.1	Implementation	204
18.2	Examples	207
18.2.1	<i>Two Blocks</i>	207
18.2.2	<i>Block and Inclined Rigid Surface – Different Boundary Condition</i>	208
18.2.3	<i>Contact Patch Test</i>	209
18.3	Inverted Contact Algorithm – Following Force	210
18.3.1	<i>Verification of the Rotational Part – Pressure on the Master Side</i>	211



<b>19</b>	<b>Lesson 9 Higher Order Mortar/STS – elmt106.f</b>	<b>213</b>
19.1	Implementation	214
19.2	Examples	217
19.2.1	<i>Two Blocks</i>	218
19.2.2	<i>Block and Inclined Rigid Surface – Different Boundary Condition</i>	219
<b>20</b>	<b>Lesson 10 3D Node-To-Segment (NTS) – elmt107.f</b>	<b>221</b>
20.1	Implementation	222
20.2	Examples	225
20.2.1	<i>Two Blocks – 3D Case</i>	226
20.2.2	<i>Sliding on a Ramp</i>	226
20.2.3	<i>Bending Over a Rigid Cylinder</i>	227
20.2.4	<i>Bending Over a Rigid Sphere</i>	227
<b>21</b>	<b>Lesson 11 Frictional Node-To-Node (NTN) – elmt108.f</b>	<b>229</b>
21.1	Implementation	230
21.2	Examples	232
21.2.1	<i>Two Blocks – Frictional Case</i>	232
21.2.2	<i>Frictional Contact Patch Test</i>	233
<b>22</b>	<b>Lesson 12 Frictional Node-To-Segment (NTS) – elmt109.f</b>	<b>235</b>
22.1	Implementation	236
22.2	Examples	240
22.2.1	<i>Two Blocks</i>	240
22.2.2	<i>Frictional Contact Patch Test</i>	241
22.2.3	<i>Block and Inclined Rigid Surface – Different Boundary Condition</i>	242
22.2.4	<i>Generalized 2D Euler–Eytelwein Problem</i>	243
<b>23</b>	<b>Lesson 13 Frictional Higher Order NTS – elmt110.f</b>	<b>245</b>
23.1	Implementation	246
23.2	Examples	250
23.2.1	<i>Two Blocks</i>	251
23.2.2	<i>Block and Inclined Rigid Surface – Different Boundary Condition</i>	252
<b>24</b>	<b>Lesson 14 Transient Contact Problems</b>	<b>255</b>
24.1	Implementation	256
24.2	Examples	257
24.2.1	<i>Block and Inclined Rigid Surface – Non-Frictional Case</i>	257
24.2.2	<i>Block and Inclined Rigid Surface – Frictional Case</i>	258
24.2.3	<i>Moving Pendulum with Impact – Center of Percussion</i>	258

<b>Appendix A</b>	<b>Numerical integration</b>	<b>261</b>
A.1	Gauss Quadrature	262
A.1.1	<i>Evaluation of Integration Points</i>	262
A.1.2	<i>Numerical Examples</i>	263
<b>Appendix B</b>	<b>Higher Order Shape Functions of Different Classes</b>	<b>265</b>
B.1	General	265
B.2	Lobatto Class	265
B.2.1	<i>1D Lobatto</i>	265
B.2.2	<i>2D Lobatto</i>	266
B.2.3	<i>Nodal FEM Input</i>	269
B.3	Bezier Class	269
B.3.1	<i>1D Bezier</i>	269
B.3.2	<i>2D Bezier</i>	270
B.3.3	<i>Nodal FEM Input</i>	272
<b>References</b>		<b>273</b>
<b>Index</b>		<b>275</b>