

Roger M. Temam, Alain M. Miranville

Mathematical Modeling in Continuum Mechanics

Second Edition

连续介质力学中的数学模型 第2版

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**MATHEMATICAL
MODELING IN
CONTINUUM MECHANICS**

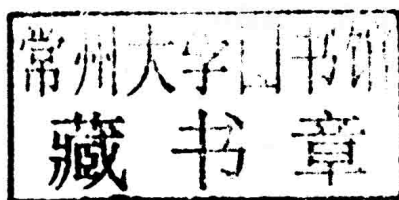
SECOND EDITION

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MATHEMATICAL MODELING IN CONTINUUM MECHANICS

SECOND EDITION

Temam and Miranville present core topics within the general themes of fluid and solid mechanics. The brisk style allows the text to cover a wide range of topics including viscous flow, magnetohydrodynamics, atmospheric flows, shock equations, turbulence, nonlinear solid mechanics, solitons, and the nonlinear Schrödinger equation.

This second edition will be a unique resource for those studying continuum mechanics at the advanced undergraduate and beginning graduate level whether in engineering, mathematics, physics, or the applied sciences. Exercises and hints for solutions have been added to the majority of chapters, and the final part on solid mechanics has been substantially expanded. These additions have now made it appropriate for use as a textbook, but it also remains an ideal reference book for students and anyone interested in continuum mechanics.

Preface

This book is an extended version of a course on continuum mechanics taught by the authors to junior graduate students in mathematics. Besides a thorough description of the fundamental parts of continuum mechanics, it contains ramifications in a number of adjacent subjects such as magnetohydrodynamics, combustion, geophysical fluid dynamics, and linear and nonlinear waves. As is, the book should appeal to a broad audience: mathematicians (students and researchers) interested in an introduction to these subjects, engineers, and scientists.

This book can be described as an “interfacial” book: interfaces between mathematics and a number of important areas of sciences. It can also be described by what it is not: it is not a book of mathematics: the mathematical language is simple, only the basic tools of calculus and linear algebra are needed. This book is not a treatise of continuum mechanics: although it contains a thorough but concise description of many subjects, it leaves aside many developments which are fundamental but not needed in practical applications and utilizations of mechanics, e.g., the intrinsic – frame invariance – character of certain quantities or the coherence of certain definitions. The reader interested by these issues is referred to the many excellent mechanics books which are available, such as those quoted in the list of references to Part I. Finally, by its size limitations, this book cannot be encyclopedic, and many choices have been made for the content; a number of subjects introduced in this book can be developed themselves into a full book. All in all, we believe that this book, benefiting from prolonged efforts and teaching experience of the authors, can be very useful to scientists who want to reduce the gap between mathematics and sciences, a gap usually due to the language barrier and the differences in thinking and reasoning.

The core of the book contains the fundamental parts of continuum mechanics: description of the motion of a continuous body, the fundamental law of

dynamics, the Cauchy and the Piola-Kirchhoff stress tensors, the constitutive laws, internal energy and the first principle of thermodynamics, shocks and the Rankine–Hugoniot relations, an introduction to fluid mechanics for inviscid and viscous Newtonian fluids, an introduction to linear elasticity and the variational principles in linear elasticity, and an introduction to nonlinear elasticity.

Besides the core of continuum mechanics, this book also contains more or less detailed introductions to several important related fields that could be themselves the subjects of separate books: magnetohydrodynamics, combustion, geophysical fluid dynamics, vibrations, linear acoustics, and nonlinear waves and solitons in the context of the Korteweg–de Vries and the nonlinear Schrödinger equations. The whole book is suitable for a one-year course at the advanced undergraduate or beginning graduate level. Parts of it are suitable for a one-semester course either on the fundamentals of continuum mechanics or on a combination of selected topics.

This second edition of the book has been augmented by the introduction of exercises and hints at solutions making it more suitable for class utilization, by a new chapter on nonlinear elasticity, and by several additions and corrections suggested by the readers of the first edition. In particular it has benefited from the comments of the anonymous and non-anonymous reviewers of the first edition, especially J. Dunwoody and J.J. Telega. The authors want also to thank P. G. Ciarlet for his comments; the new chapter on nonlinear elasticity borrowed very much from his classical book on the subject. Finally they gratefully acknowledge essential help in the production of the volume from Teresa Bunge, Jacques Laminie, Eric Simonnet, and Djoko Wirosoetisno.

Roger Temam
Alain Miranville
June 2004

A few words about notations

The notations in this book are not uniform; this is partly done on purpose and partly because we had no choice. Indeed modelers usually have to comply or at least adapt to the notations common in a given field, and thus they must be trained to some flexibility. Another reason for having non-uniform notations is that different fields are present in this volume, and it was not possible to find notations fitting “all the standards.”

Another objective while deciding the notations was to choose notations that can be easily reproduced by handwriting, thus avoiding as much as possible arrows, boldfaced type, and simple and double underlining with bars or tildes; in general, in a given chapter of this book, in a given context, it is clear what a given symbol represents.

Although the notations are not rigid, there are still some repeated patterns in the notations, and we indicate hereafter notations used in several chapters:

Ω or \mathcal{O} , possibly with indices: domain in \mathbb{R}^2 or \mathbb{R}^3

$x = (x_1, x_2)$ or (x_1, x_2, x_3) : generic point in \mathbb{R}^2 or \mathbb{R}^3 . Also denoted (x, y) or (x, y, z)

$a = (a_1, a_2)$ or (a_1, a_2, a_3) : initial position in Lagrangian variables

t : time

$u = (u_1, u_2)$ or (u_1, u_2, u_3) , or v or w : vectors in \mathbb{R}^2 or \mathbb{R}^3 . Also denoted (u, v) or (u, v, w)

AB (or \overrightarrow{AB} to emphasize): vector from A to B

u or U : velocity

u : displacement vector

γ : acceleration

m : mass

f, F : forces; usually f for volume forces and F for surface forces

ρ : density

g : gravity constant. Also used for equation of state for fluids

T or θ : temperature

σ : Cauchy stress tensor (in general)

n : unit outward normal on the boundary of an open set Ω or \mathcal{O} , $n = (n_1, n_2)$
or $n = (n_1, n_2, n_3)$

We will use also the following classical symbols and notations:

δ_{ij} : the Kronecker symbol equal to 1 if $i = j$ and to 0 if $i \neq j$

$\varphi_{,i}$ will denote the partial derivative $\partial\varphi/\partial x_i$.

The Einstein summation convention will be used: when an index (say j) is repeated in a mathematical symbol or within a product of such symbols, we add these expressions for $j = 1, 2, 3$. Hence

$$\sigma_{ij,j} = \sum_{j=1}^3 \frac{\partial \sigma_{ij}}{\partial x_j}, \quad \sigma_{ij} \cdot n_j = \sum_{j=1}^3 \sigma_{ij} n_j.$$

Contents

<i>Preface</i>	page ix
<i>A few words about notations</i>	xi

PART I FUNDAMENTAL CONCEPTS IN CONTINUUM MECHANICS

1 Describing the motion of a system: geometry and kinematics	3
1.1 Deformations	3
1.2 Motion and its observation (kinematics)	6
1.3 Description of the motion of a system: Eulerian and Lagrangian derivatives	10
1.4 Velocity field of a rigid body: helicoidal vector fields	13
1.5 Differentiation of a volume integral depending on a parameter	18
2 The fundamental law of dynamics	24
2.1 The concept of mass	24
2.2 Forces	30
2.3 The fundamental law of dynamics and its first consequences	32
2.4 Application to systems of material points and to rigid bodies	34
2.5 Galilean frames: the fundamental law of dynamics expressed in a non-Galilean frame	38
3 The Cauchy stress tensor and the Piola-Kirchhoff tensor. Applications	42
3.1 Hypotheses on the cohesion forces	42
3.2 The Cauchy stress tensor	45
3.3 General equations of motion	48
3.4 Symmetry of the stress tensor	50
3.5 The Piola-Kirchhoff tensor	52

4	Real and virtual powers	57
4.1	Study of a system of material points	57
4.2	General material systems: rigidifying velocities	61
4.3	Virtual power of the cohesion forces: the general case	63
4.4	Real power: the kinetic energy theorem	67
5	Deformation tensor, deformation rate tensor, constitutive laws	70
5.1	Further properties of deformations	70
5.2	The deformation rate tensor	75
5.3	Introduction to rheology: the constitutive laws	77
5.4	Appendix. Change of variable in a surface integral	87
6	Energy equations and shock equations	90
6.1	Heat and energy	90
6.2	Shocks and the Rankine–Hugoniot relations	95
PART II PHYSICS OF FLUIDS		
7	General properties of Newtonian fluids	103
7.1	General equations of fluid mechanics	103
7.2	Statics of fluids	109
7.3	Remark on the energy of a fluid	114
8	Flows of inviscid fluids	116
8.1	General theorems	116
8.2	Plane irrotational flows	120
8.3	Transsonic flows	130
8.4	Linear acoustics	134
9	Viscous fluids and thermohydraulics	137
9.1	Equations of viscous incompressible fluids	137
9.2	Simple flows of viscous incompressible fluids	138
9.3	Thermohydraulics	144
9.4	Equations in nondimensional form: similarities	146
9.5	Notions of stability and turbulence	148
9.6	Notion of boundary layer	152
10	Magnetohydrodynamics and inertial confinement of plasmas	158
10.1	The Maxwell equations and electromagnetism	159
10.2	Magnetohydrodynamics	163
10.3	The Tokamak machine	165
11	Combustion	172
11.1	Equations for mixtures of fluids	172

11.2	Equations of chemical kinetics	174
11.3	The equations of combustion	176
11.4	Stefan–Maxwell equations	178
11.5	A simplified problem: the two-species model	181
12	Equations of the atmosphere and of the ocean	185
12.1	Preliminaries	186
12.2	Primitive equations of the atmosphere	188
12.3	Primitive equations of the ocean	192
12.4	Chemistry of the atmosphere and the ocean	193
	Appendix. The differential operators in spherical coordinates	195
PART III SOLID MECHANICS		
13	The general equations of linear elasticity	201
13.1	Back to the stress–strain law of linear elasticity: the elasticity coefficients of a material	201
13.2	Boundary value problems in linear elasticity: the linearization principle	203
13.3	Other equations	208
13.4	The limit of elasticity criteria	211
14	Classical problems of elastostatics	215
14.1	Longitudinal traction–compression of a cylindrical bar	215
14.2	Uniform compression of an arbitrary body	218
14.3	Equilibrium of a spherical container subjected to external and internal pressures	219
14.4	Deformation of a vertical cylindrical body under the action of its weight	223
14.5	Simple bending of a cylindrical beam	225
14.6	Torsion of cylindrical shafts	229
14.7	The Saint-Venant principle	233
15	Energy theorems, duality, and variational formulations	235
15.1	Elastic energy of a material	235
15.2	Duality – generalization	237
15.3	The energy theorems	240
15.4	Variational formulations	243
15.5	Virtual power theorem and variational formulations	246
16	Introduction to nonlinear constitutive laws and to homogenization	248
16.1	Nonlinear constitutive laws (nonlinear elasticity)	249

16.2	Nonlinear elasticity with a threshold (Henky's elastoplastic model)	251
16.3	Nonconvex energy functions	253
16.4	Composite materials: the problem of homogenization	255
17	Nonlinear elasticity and an application to biomechanics	259
17.1	The equations of nonlinear elasticity	259
17.2	Boundary conditions – boundary value problems	262
17.3	Hyperelastic materials	264
17.4	Hyperelastic materials in biomechanics	266
PART IV INTRODUCTION TO WAVE PHENOMENA		
18	Linear wave equations in mechanics	271
18.1	Returning to the equations of linear acoustics and of linear elasticity	271
18.2	Solution of the one-dimensional wave equation	275
18.3	Normal modes	276
18.4	Solution of the wave equation	281
18.5	Superposition of waves, beats, and packets of waves	285
19	The soliton equation: the Korteweg–de Vries equation	289
19.1	Water-wave equations	290
19.2	Simplified form of the water-wave equations	292
19.3	The Korteweg–de Vries equation	295
19.4	The soliton solutions of the KdV equation	299
20	The nonlinear Schrödinger equation	303
20.1	Maxwell equations for polarized media	304
20.2	Equations of the electric field: the linear case	306
20.3	General case	309
20.4	The nonlinear Schrödinger equation	313
20.5	Soliton solutions of the NLS equation	316
Appendix. The partial differential equations of mechanics		319
Hints for the exercises		321
<i>References</i>		332
<i>Index</i>		337

PART I

**FUNDAMENTAL CONCEPTS
IN CONTINUUM MECHANICS**

CHAPTER ONE

Describing the motion of a system: geometry and kinematics

1.1. Deformations

The purpose of mechanics is to study and describe the motion of material systems. The language of mechanics is very similar to that of set theory in mathematics: we are interested in material bodies or systems, which are made of material points or matter particles. A material system fills some part (a subset) of the ambient space (\mathbb{R}^3), and the position of a material point is given by a point in \mathbb{R}^3 ; a part of a material system is called a subsystem.

We will almost exclusively consider material bodies that fill a domain (i.e., a connected open set) of the space. We will not study the mechanically important cases of thin bodies that can be modeled as a surface (plates, shells) or as a line (beams, cables). The modeling of the motion of such systems necessitates hypotheses that are very similar to the ones we will present in this book, but we will not consider these cases here.

A material system fills a domain Ω_0 in \mathbb{R}^3 at a given time t_0 . After deformation (think, for example, of a fluid or a tennis ball), the system fills a domain Ω in \mathbb{R}^3 . A material point, whose initial position is given by the point $a \in \Omega_0$, will be, after transformation, at the point $x \in \Omega$.

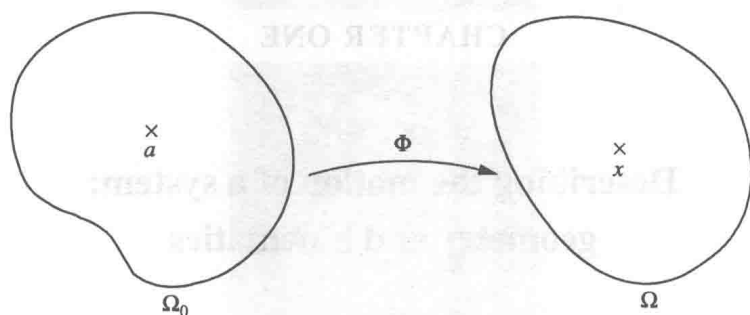
The deformation can thus be characterized by a mapping as follows (see Figure 1.1):

$$\Phi: a \in \Omega_0 \mapsto x \in \Omega.$$

Assuming that matter is conserved during the deformation, we are led to make the following natural hypothesis:

The function Φ is one – to – one from Ω_0 onto Ω .

We will further assume that the deformation Φ is a smooth application of class \mathcal{C}^1 at least, from Ω_0 into Ω , as well as its inverse (\mathcal{C}^1 from Ω onto Ω_0). In fact we assume that Φ is as smooth as needed.

Figure 1.1 The mapping Φ .

Regularity assumption

The regularity assumption made on Φ will actually be general; we will assume that all the functions we introduce are as regular as needed for all the mathematical operations performed to be justified (e.g., integration by parts, differentiation of an integral depending on a parameter, etc.). This hypothesis, which will be constantly assumed in the following, will only be weakened in Chapter 6 for the study of shock waves, which correspond to the appearance of discontinuity surfaces. In that case, we will assume that the map Φ is piecewise C^1 . This assumption must be weakened also for the study of other phenomena which will not be considered here, such as singular vortices for fluids, dislocations for solids, or collisions of rigid bodies.

Let $\text{grad } \Phi(a) = \nabla \Phi(a)$ be the matrix whose entries are the quantities $(\partial \Phi_i / \partial a_j)(a)$; this is the Jacobian matrix of the mapping $a \mapsto x$ also denoted sometimes Dx/Da . Because Φ^{-1} is differentiable, the Jacobian det $(\nabla \Phi)$ of the transformation $a \mapsto x$ is necessarily different from zero. We will assume in the following that it is strictly positive; the negative sign corresponds to the nonphysical case of a change of orientation (a left glove becoming a right glove). We will later study the role played by the linear tangent map at point a in relation to the Taylor formula

$$\Phi(a) = \Phi(a_0) + \nabla \Phi(a_0) \cdot (a - a_0) + o(|a - a_0|).$$

We will also introduce the dilation tensor to study the deformation of a “small” tetrahedron.

Displacement

Definition 1.1. The map $u : a \mapsto x - a = \Phi(a) - a$ is called the displacement; $u(a)$ is the displacement of the particle a .