An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

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INRIA Rhône–Alpes, Grenoble.


Joint work with O. Brüls, Q.Z. Chen and G. Virlez (Université de Liège)
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction

Bio.

Team-Project BIPOP. INRIA. Centre de Grenoble Rhône–Alpes

▶ Scientific leader : Bernard Brogliato
▶ 8 permanents, 5 PhD, 4 Post-docs, 3 Engineer,
▶ Nonsmooth dynamical systems : Modeling, analysis, simulation and Control.
▶ Nonsmooth Optimization : Analysis & algorithms.

Personal research themes

▶ Nonsmooth Dynamical systems. Higher order Moreau’s sweeping process. Complementarity systems and Filippov systems
▶ Modeling and simulation of switched electrical circuits
▶ Discretization method for sliding mode control and Optimal control.
▶ Formulation and numerical solvers for Coulomb’s friction and Signorini’s problem. Second order cone programming.
▶ Time–integration techniques for nonsmooth mechanical systems : Mixed higher order schemes, Time–discontinuous Galerkin methods, Projected time–stepping schemes and generalized α–schemes.
An extension of the Moreau–Jean scheme based on the generalized-$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction.

Mechanical systems with contact, impact and friction

Simulation of Circuit breakers (INRIA/Schneider Electric)

Flexible multibody systems.
Mechanical systems with contact, impact and friction

Simulation of the ExoMars Rover (INRIA/Trasys Space/ESA)
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

Mechanical systems with contact, impact and friction

Simulation of wind turbines (DYNAMIND project)
Joint work with O. Brüls, Q.Z. Chen and G. Virlez (Université de Liège)

Flexible multibody systems.
An extension of the Moreau–Jean scheme based on the generalized–\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction.

**Mechanical systems with contact, impact and friction**

Simulation of Tilt rotor. (Politecnico di Milano, Masarati, P.)

Flexible multibody systems.
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

Objectives & Motivations

Outline

▶ Basic facts on nonsmooth dynamics and its time integration
  ▶ Measure differential inclusion
  ▶ Time–stepping schemes (Moreau–Jean and Schatzman–Paoli)
▶ Newmark based schemes for nonsmooth dynamics
  ▶ Splitting impulsive and non impulsive forces
  ▶ Velocity level constraints and impact law
▶ Simple Energy Analysis
▶ Impact in flexible structures
  ▶ jump in velocity or standard impact ?
  ▶ coefficient of restitution in flexible structure.
Objectives & Motivations

Problem setting
Measures Decomposition

The Moreau’s sweeping process
State–of–the–art

Background

- Newmark’s scheme.
- HHT scheme
- Generalized $\alpha$-methods

Newmark’s scheme and the $\alpha$–methods family

Nonsmooth Newmark’s scheme

- Time–continuous energy balance equations
- Energy analysis for Moreau–Jean scheme
- Energy Analysis for the nonsmooth Newmark scheme

Energy Analysis

- The impacting beam benchmark

Discussion and FEM applications
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction.

**Background**

**Problem setting**

**NonSmooth Multibody Systems**

**Scleronomous holonomic perfect unilateral constraints**

\[
\begin{cases}
M(q(t))\dot{v} = F(t, q(t), v(t)) + G(q(t))\lambda(t), \text{ a.e } \\
\dot{q}(t) = v(t), \\
g(t) = g(q(t)), \quad \dot{g}(t) = G^T(q(t))v(t), \\
0 \leq g(t) \perp \lambda(t) \geq 0, \\
\dot{g}^+(t) = -e\dot{g}^-(t),
\end{cases}
\]

where \(G(q) = \nabla g(q)\) and \(e\) is the coefficient of restitution.
Unilateral constraints as an inclusion

Definition (Perfect unilateral constraints on the smooth dynamics)

\[
\begin{align*}
\dot{q} &= v \\
M(q) \frac{dv}{dt} + F(t, q, v) &= r \\
-r &\in N_{C(t)}(q(t))
\end{align*}
\]

(2)

where \( r \) is the generalized force or generalized reaction due to the constraints.

Remark

- The unilateral constraints are said to be perfect due to the normality condition.
- Notion of normal cones can be extended to more general sets. See (Clarke, 1975, 1983; Mordukhovich, 1994)
- When \( C(t) = \{ q \in \mathbb{R}^n, g_{\alpha}(q, t) \geq 0, \alpha \in \{ 1 \ldots \nu \} \} \), the multipliers \( \lambda \in \mathbb{R}^m \) such that \( r = \nabla_T^T g(q, t) \lambda \).
Nonsmooth Lagrangian Dynamics

Fundamental assumptions.

- The velocity $v = \dot{q}$ is of Bounded Variations (B.V)
  - The equation are written in terms of a right continuous B.V. (R.C.B.V.) function, $v^+$ such that
  $$v^+ = \dot{q}^+ \quad (3)$$

- $q$ is related to this velocity by
  $$q(t) = q(t_0) + \int_{t_0}^{t} v^+(t) \, dt \quad (4)$$

- The acceleration, ($\ddot{q}$ in the usual sense) is hence a differential measure $dv$ associated with $v$ such that
  $$dv([a, b]) = \int_{[a, b]} dv = v^+(b) - v^+(a) \quad (5)$$
Nonsmooth Lagrangian Dynamics

Definition (Nonsmooth Lagrangian Dynamics)

\[
\begin{align*}
M(q)dv + F(t, q, v^+)dt &= di \\
v^+ &= \dot{q}^+
\end{align*}
\] (6)

where \( di \) is the reaction measure and \( dt \) is the Lebesgue measure.

Remarks

- The nonsmooth Dynamics contains the impact equations and the smooth evolution in a single equation.
- The formulation allows one to take into account very complex behaviors, especially, finite accumulation (Zeno-state).
- This formulation is sound from a mathematical Analysis point of view.

References

An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

**Background**

**Measures Decomposition**

**Nonsmooth Lagrangian Dynamics**

**Measures Decomposition (for dummies)**

\[
\begin{align*}
\frac{dv}{dt} &= \gamma dt + (v^+ - v^-) d\nu + dv_s \\
\frac{di}{dt} &= f dt + p d\nu + di_s
\end{align*}
\] (7)

where

- $\gamma = \ddot{q}$ is the acceleration defined in the usual sense.
- $f$ is the Lebesgue measurable force,
- $v^+ - v^-$ is the difference between the right continuous and the left continuous functions associated with the B.V. function $v = \dot{q}$,
- $d\nu$ is a purely atomic measure concentrated at the time $t_i$ of discontinuities of $v$, i.e. where $(v^+ - v^-) \neq 0$, i.e. $d\nu = \sum_i \delta_{t_i}$
- $p$ is the purely atomic impact percussions such that $p d\nu = \sum_i p_i \delta_{t_i}$
- $dv_s$ and $di_s$ are singular measures with the respect to $dt + d\eta$. 

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Background – 10/74
Impact equations and Smooth Lagrangian dynamics

Substituting the decomposition of measures into the nonsmooth Lagrangian Dynamics, one obtains

**Definition (Impact equations)**

\[ M(q)(v^+ - v^-)d\nu = pd\nu, \]  
(8)

or

\[ M(q(t_i))(v^+(t_i) - v^-(t_i)) = p_i, \]  
(9)

**Definition (Smooth Dynamics between impacts)**

\[ M(q)\gamma dt + F(t, q, v)dt = fdt \]  
(10)

or

\[ M(q)\gamma^+ + F(t, q, v^+) = f^+ [dt - a.e.] \]  
(11)
The Moreau’s sweeping process of second order

Definition (Moreau (1983, 1988))

A key stone of this formulation is the inclusion in terms of velocity. Indeed, the inclusion (2) is “replaced” by the following inclusion

\[
\begin{align*}
M(q)dv + F(t, q, v^+)dt &= di \\
\dot{v}^+ &= \dot{q}^+ \\
-di &\in N_{TC}(q)(v^+)
\end{align*}
\]  

Comments

This formulation provides a common framework for the nonsmooth dynamics containing inelastic impacts without decomposition.

Foundation for the Moreau–Jean time–stepping approach.
The Moreau’s sweeping process of second order

Comments

- The inclusion concerns measures. Therefore, it is necessary to define what is the inclusion of a measure into a cone.
- The inclusion in terms of velocity $v^+$ rather than of the coordinates $q$.

Interpretation

- Inclusion of measure, $-di \in K$
  - Case $di = r'dt = fdt$.
    - $-f \in K$ (13)
  - Case $di = p_i\delta_i$.
    - $-p_i \in K$ (14)

- Inclusion in terms of the velocity. Viability Lemma
  If $q(t_0) \in C(t_0)$, then
  \[ v^+ \in T_C(q), \quad t \geq t_0 \Rightarrow q(t) \in C(t), \quad t \geq t_0 \]
  The unilateral constraints on $q$ are satisfied. The equivalence needs at least an impact inelastic rule.
The Moreau’s sweeping process of second order

**The Newton-Moreau impact rule**

\[-d_i \in N_{T_C(q(t))}(v^+(t) + ev^-(t))\]  
(15)

where \(e\) is a coefficient of restitution.

**Velocity level formulation. Index reduction**

\[
0 \leq y \perp \lambda \geq 0
\]
\[
\begin{align*}
-\lambda & \in N_{R^+}(y) \\
-\lambda & \in N_{T_{R^+}(y)}(\dot{y})
\end{align*}
\]
if \(y \leq 0\) then \(0 \leq \dot{y} \perp \lambda \geq 0\)

(16)
The Moreau's sweeping process of second order

The case of $C$ is finitely represented

\[ C = \{ q \in \mathcal{M}(t), g_{\alpha}(q) \geq 0, \alpha \in \{1 \ldots \nu\} \}. \quad (17) \]

Decomposition of $d_i$ and $v^+$ onto the tangent and the normal cone.

\[ d_i = \sum_{\alpha} \nabla^T_q g_{\alpha}(q) \, d\lambda_{\alpha} \quad (18) \]

\[ U_{\alpha}^+ = \nabla_q g_{\alpha}(q) \, v^+, \alpha \in \{1 \ldots \nu\} \quad (19) \]

Complementarity formulation (under constraints qualification condition)

\[ -d\lambda_{\alpha} \in N_{T_{\mathbb{R}^+}}(g_{\alpha})(U_{\alpha}^+) \iff \text{if } g_{\alpha}(q) \leq 0, \text{ then } 0 \leq U_{\alpha}^+ \perp d\lambda_{\alpha} \geq 0 \quad (20) \]

The case of $C$ is $\mathbb{R}^+$

\[ -d_i \in N_C(q) \iff 0 \leq q \perp d_i \geq 0 \quad (21) \]

is replaced by

\[ -d_i \in N_{T_C(q)}(v^+) \iff \text{if } q \leq 0, \text{ then } 0 \leq v^+ \perp d_i \geq 0 \quad (22) \]
Principle of nonsmooth event capturing methods (Time-stepping schemes)

1. A unique formulation of the dynamics is considered. For instance, a dynamics in terms of measures.
   \[
   \begin{cases}
   -md\mathbf{u} = d\mathbf{r} \\
   \mathbf{q} = \dot{\mathbf{u}}^+ \\
   0 \leq dr \perp \dot{u}^+ \geq 0 \text{ if } \mathbf{q} \leq 0
   \end{cases}
   \] (23)

2. The time-integration is based on a consistent approximation of the equations in terms of measures. For instance,
   \[
   \int_{t_k}^{t_{k+1}} d\mathbf{u} = \int_{t_k}^{t_{k+1}} d\mathbf{u} = (\mathbf{v}^+(t_{k+1}) - \mathbf{v}^+(t_k)) \approx (\mathbf{u}_{k+1} - \mathbf{u}_k) \] (24)

3. Consistent approximation of measure inclusion.
   \[
   -d\mathbf{r} \in N_{K(t)}(\mathbf{u}^+(t)) \quad (25) \quad \Rightarrow \quad \begin{cases}
   p_{k+1} \approx \int_{t_k}^{t_{k+1}} d\mathbf{r} \\
   p_{k+1} \in N_{K(t)}(\mathbf{u}_{k+1})
   \end{cases}
   \] (26)
State-of-the-art

Numerical time-integration methods for Nonsmooth Multibody systems (NSMBS):

Nonsmooth event capturing methods (Time-stepping methods)

- robust, stable and proof of convergence
- low kinematic level for the constraints
- able to deal with finite accumulation
- very low order of accuracy even in free flight motions

Two main implementations

- Moreau–Jean time-stepping scheme
- Schatzman–Paoli time-stepping scheme
An extension of the Moreau–Jean scheme based on the generalized–\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction.

The Moreau’s sweeping process

State–of–the–art

Moreau’s Time stepping scheme (Moreau, 1988 ; Jean, 1999)

Principle

\[
\begin{align*}
M(q_{k+\theta})(v_{k+1} - v_k) - hF_{k+\theta} &= p_{k+1} = G(q_{k+\theta})P_{k+1}, \\
q_{k+1} &= q_k + hv_{k+\theta}, \\
U_{k+1} &= G^T(q_{k+\theta})v_{k+1} \\
0 &\leq U_{k+1}^\alpha + eU_k^\alpha \perp P_{k+1}^\alpha \geq 0 \quad \text{if} \quad \bar{g}_{k,\gamma}^\alpha \leq 0 \\
P_{k+1}^\alpha &= 0 \quad \text{otherwise}
\end{align*}
\]

(27a)

(27b)

(27c)

(27d)

with

- \(\theta \in [0, 1]\)
- \(x_{k+\theta} = (1 - \theta)x_{k+1} + \theta x_k\)
- \(F_{k+\theta} = F(t_k\theta, q_{k+\theta}, v_{k+\theta})\)
- \(\bar{g}_{k,\gamma} = g_k + \gamma hU_k, \gamma \geq 0\) is a prediction of the constraints.
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction

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Schatzman’s Time stepping scheme (Paoli and Schatzman, 2002)

Principle

\[
\begin{align}
M(q_{k+1})(q_{k+1} - 2q_k + q_{k-1}) - h^2 F_{k+\theta} &= p_{k+1}, \\
\nu_{k+1} &= \frac{q_{k+1} - q_{k-1}}{2h}, \\
-p_{k+1} &\in N_K \left( \frac{q_{k+1} + eq_{k-1}}{1 + e} \right),
\end{align}
\]

where \( N_K \) defined the normal cone to \( K \).

For \( K = \{ q \in \mathbb{R}^n, y = g(q) \geq 0 \} \)

\[
0 \leq g \left( \frac{q_{k+1} + eq_{k-1}}{1 + e} \right) \perp \nabla g \left( \frac{q_{k+1} + eq_{k-1}}{1 + e} \right) P_{k+1} \geq 0
\]
Comparison

Shared mathematical properties

- Convergence results for one constraints
- Convergence results for multiple constraints problems with acute kinetic angles
- No theoretical proof of order

Mechanical properties

- Position vs. velocity constraints
- Respect of the impact law in one step (Moreau) vs. Two-steps(Schatzman)
- Linearized constraints rather than nonlinear.

But
Both schemes do not are quite inaccurate and “dissipate” a lot of energy of vibrations. This is a consequence of the first order approximation of the smooth forces term $F.$
Objectives & Motivations
  Problem setting
  Measures Decomposition

The Moreau’s sweeping process
  State–of–the–art

Background
  Newmark’s scheme.
  HHT scheme
  Generalized $\alpha$-methods

Newmark’s scheme and the $\alpha$–methods family

Nonsmooth Newmark’s scheme
  Time–continuous energy balance equations
  Energy analysis for Moreau–Jean scheme
  Energy Analysis for the nonsmooth Newmark scheme

Energy Analysis
  The impacting beam benchmark

Discussion and FEM applications
The Newmark scheme

Linear Time “Invariant” Dynamics without contact

\[
\begin{align*}
M\ddot{q}(t) + Kq(t) + Cv(t) &= f(t) \\
\dot{q}(t) &= v(t)
\end{align*}
\] (30)
The Newmark scheme (Newmark, 1959)

**Principle**

Given two parameters $\gamma$ and $\beta$

\[
\begin{align*}
Ma_{k+1} &= f_{k+1} - Kq_{k+1} - Cv_{k+1} \\
v_{k+1} &= v_k + ha_{k+\gamma} \\
q_{k+1} &= q_k + hv_k + \frac{h^2}{2}a_{k+2\beta}
\end{align*}
\]

(31)

**Notations**

\[
\begin{align*}
f(t_{k+1}) &= f_{k+1}, \quad x_{k+1} &\approx x(t_{k+1}), \\
x_{k+\gamma} &= (1 - \gamma)x_k + \gamma x_{k+1}
\end{align*}
\]

(32)
The Newmark scheme

Implementation

Let us consider the following explicit prediction

\[
\begin{align*}
    v_k^* &= v_k + h(1 - \gamma)a_k \\
    q_k^* &= q_k + hv_k + \frac{1}{2}(1 - 2\beta)h^2a_k
\end{align*}
\]  (33)

The Newmark scheme may be written as

\[
\begin{align*}
    a_{k+1} &= \hat{M}^{-1}(\text{-}Kq_k^* - Cv_k^* + f_{k+1}) \\
    v_{k+1} &= v_k^* + h\gamma a_{k+1} \\
    q_{k+1} &= q_k^* + h^2\beta a_{k+1}
\end{align*}
\]  (34)

with the iteration matrix

\[
\hat{M} = M + h^2\beta K + \gamma hC
\]  (35)
The Newmark scheme

Properties

▶ One–step method in state. (Two steps in position)
▶ Second order accuracy if and only if $\gamma = \frac{1}{2}$
▶ Unconditional stability for $2\beta \geq \gamma \geq \frac{1}{2}$

<table>
<thead>
<tr>
<th>Average acceleration</th>
<th>Implicit</th>
<th>$\gamma = \frac{1}{2} \text{ and } \beta = \frac{1}{4}$</th>
</tr>
</thead>
<tbody>
<tr>
<td>(Trapezoidal rule)</td>
<td></td>
<td></td>
</tr>
<tr>
<td>central difference</td>
<td>Explicit</td>
<td>$\gamma = \frac{1}{2} \text{ and } \beta = 0$</td>
</tr>
<tr>
<td>linear acceleration</td>
<td>Implicit</td>
<td>$\gamma = \frac{1}{2} \text{ and } \beta = \frac{1}{6}$</td>
</tr>
<tr>
<td>Fox–Goodwin</td>
<td>Implicit</td>
<td>$\gamma = \frac{1}{2} \text{ and } \beta = \frac{1}{12}$</td>
</tr>
<tr>
<td>(Royal Road)</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Table: Standard values for Newmark scheme ((Hughes, 1987, p 493)Géradin and Rixen (1993))
An extension of the Moreau–Jean scheme based on the generalized–\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction

Newmark’s scheme and the \(\alpha\)–methods family

Newmark’s scheme.

The Newmark scheme

High frequencies dissipation

- In flexible multibody Dynamics or in standard structural dynamics discretized by FEM, high frequency oscillations are artifacts of the semi-discrete structures.
- In Newmark’s scheme, maximum high frequency damping is obtained with

\[
\gamma \gg \frac{1}{2}, \quad \beta = \frac{1}{4}(\gamma + \frac{1}{2})^2
\]

example for \(\gamma = 0.9, \beta = 0.49\)
An extension of the Moreau–Jean scheme based on the generalized–\( \alpha \) schemes for the numerical time integration of flexible dynamical systems with contact and friction.

Newmark’s scheme and the \( \alpha \)–methods family

Newmark’s scheme.

The Newmark scheme

From (Hughes, 1987):

![Graph showing spectral radii for Newmark methods for varying \( \beta \) [9].](image)

**Figure 9.1.3** Spectral radii for Newmark methods for varying \( \beta \) [9].
An extension of the Moreau–Jean scheme based on the generalized–\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction

Newmark’s scheme and the \(\alpha\)–methods family

HHT scheme

The Hilber–Hughes–Taylor scheme. Hilber et al. (1977)

Objectives

- to introduce numerical damping without dropping the order to one.

Principle

Given three parameters \(\gamma\), \(\beta\) and \(\alpha\) and the notation

\[
M\ddot{q}_{k+1} = -(Kq_{k+1} + Cv_{k+1}) + F_{k+1} \tag{37}
\]

\[
\begin{align*}
M_{k+1} &= M_{\dot{q}_{k+1}-\alpha} = -(Kq_{k+1-\alpha} + Cv_{k+1-\alpha}) + F_{k+1-\alpha} \\
v_{k+1} &= v_k + ha_{k+\gamma} \\
q_{k+1} &= q_k + hv_k + \frac{h^2}{2} a_{k+2\beta}
\end{align*}
\]

Standard parameters (Hughes, 1987, p532) are

\[
\alpha \in [0, 1/3], \gamma = 1/2 + \alpha \text{ and } \beta = (1/2 + \alpha)^2/4 \tag{39}
\]

Warning

The notation are abusive. \(a_{k+1}\) is not the approximation of the acceleration at \(t_{k+1}\)
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

- Newmark’s scheme and the $\alpha$–methods family
- HHT scheme

The HHT scheme

Properties

- Two–step method in state. (Three–steps method in position)
- Unconditional stability and second order accuracy with the previous rule. (39)
- For $\alpha = 0$, we get the trapezoidal rule and the numerical dissipation increases with $|\alpha|$. 
The HHT scheme

From (Hughes, 1987), with $\alpha \rightarrow -\alpha$:

![Graph showing spectral radii for alpha-methods, optimal collocation schemes, and Houbolt, Newmark, Park, and Wilson methods.](image)

Figure 9.3.1  Spectral radii for $\alpha$-methods, optimal collocation schemes, and Houbolt, Newmark, Park, and Wilson methods [22].
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

Newmark’s scheme and the $\alpha$–methods family

Generalized $\alpha$-methods (Chung and Hulbert, 1993)

Principle

Given three parameters $\gamma$, $\beta$, $\alpha_m$ and $\alpha_f$ and the notation

$$M\ddot{q}_{k+1} = -(Kq_{k+1} + Cv_{k+1}) + F_{k+1}$$  \hspace{1cm} (40)

$$\begin{cases}
Ma_{k+1} - \alpha_m = M\ddot{q}_{k+1} - \alpha_f \\
v_{k+1} = v_k + ha_{k+1} \\
q_{k+1} = q_k + hv_k + \frac{h^2}{2} a_{k+2} \beta 
\end{cases}$$ \hspace{1cm} (41)

Standard parameters (Chung and Hulbert, 1993) are chosen as

$$\alpha_m = \frac{2\rho_{\infty} - 1}{\rho_{\infty} + 1}, \quad \alpha_f = \frac{\rho_{\infty}}{\rho_{\infty} + 1}, \quad \gamma = \frac{1}{2} + \alpha_f - \alpha_m \quad \text{and} \quad \beta = \frac{1}{4} (\gamma + \frac{1}{2})^2$$ \hspace{1cm} (42)

where $\rho_{\infty} \in [0, 1]$ is the spectral radius of the algorithm at infinity.
Generalized \(\alpha\)-methods (Chung and Hulbert, 1993)

Properties

- Two–step method in state.
- Unconditional stability and second order accuracy.
- Optimal combination of accuracy at low-frequency and numerical damping at high-frequency.

Special cases

- \(\alpha_m = \alpha_f = 0\). Newmark scheme
- \(\alpha_m = 0\) and \(\alpha_f = \alpha\) HHT scheme.
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Energy Analysis
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Discussion and FEM applications
A first naive approach

Direct Application of the HHT scheme to Linear Time “Invariant” Dynamics with contact

\[
\begin{align*}
M\ddot{v}(t) + Kq(t) + Cv(t) &= f(t) + r(t), \text{ a.e} \\
\dot{q}(t) &= v(t) \\
r(t) &= G(q)\lambda(t) \\
g(t) &= g(q(t)), \quad \dot{g}(t) = G^T(q(t))v(t), \\
0 &\leq g(t) \perp \lambda(t) \geq 0,
\end{align*}
\] (43)

results in

\[
\begin{align*}
M\ddot{q}_{k+1} &= -(Kq_{k+1} + Cv_{k+1}) + F_{k+1} + r_{k+1} \\
r_{k+1} &= G_{k+1}\lambda_{k+1}
\end{align*}
\] (44)

\[
\begin{align*}
Ma_{k+1} &= M\ddot{q}_{k+1} + \alpha \\
v_{k+1} &= v_k + ha_{k+\gamma} \\
q_{k+1} &= q_k + hv_k + \frac{h^2}{2}a_{k+2\beta} \\
0 &\leq g_{k+1} \perp \lambda_{k+1} \geq 0,
\end{align*}
\] (45)
A first naive approach

**Direct Application of the HHT scheme to Linear Time “Invariant” Dynamics with contact**

The scheme is not consistent for mainly two reasons:

- If an impact occur between rigid bodies, or if a restitution law is needed which is mandatory between semidiscrete structure, the impact law is not taken into account by the discrete constraint at position level

- Even if the constraint is discretized at the velocity level, i.e.

\[
\text{if } \bar{g}_{k+1}, \text{ then } 0 \leq \dot{g}_{k+1} + e g_k \perp \lambda_{k+1} \geq 0
\]  

(46)

the scheme is consistent only for \( \gamma = 1 \) and \( \alpha = 0 \) (first order approximation.)
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction

A first naive approach

Velocity based constraints with standard Newmark scheme ($\alpha = 0.0$)

Bouncing ball example. $m = 1$, $g = 9.81$, $x_0 = 1.0$, $v_0 = 0.0$, $e = 0.9$

$h = 0.001$, $\gamma = 1.0$, $\beta = \gamma/2$  

$h = 0.001$, $\gamma = 1/2$, $\beta = \gamma/2$
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction.

A first naive approach

Position based constraints with standard Newmark scheme ($\alpha = 0.0$)

Bouncing ball example. $m = 1$, $g = 9.81$, $v_0 = 0.0$, $e = 0.9$, $h = 0.001$, $\gamma = 1.0$, $\beta = \gamma / 2$

$x_0 = 1.0$

$x_0 = 1.01$
The nonsmooth generalized $\alpha$ scheme

Dynamics with contact and (possibly) impact

\[
\begin{align*}
M \, dv &= F(t, q, v) \, dt + G(q) \, di \\
\dot{q}(t) &= v^+(t), \\
g(t) &= g(q(t)), \quad \dot{g}(t) = G^T(q(t))v(t), \\
\text{if } g(t) \leq 0, \quad 0 \leq g^+(t) + \dot{e}g^-(t) \perp di \geq 0,
\end{align*}
\] (47)
The nonsmooth generalized $\alpha$ scheme

Splitting the dynamics between smooth and nonsmooth part

$$M dv = M\ddot{v}(t) dt + M dW$$  \hfill (48)

with

$$\begin{cases} M\ddot{v} dt = F(t, q, v) dt \\ M dW = G(q) di \end{cases}$$ \hfill (49)

Different choices for the discrete approximation of the term $Ma dt$ and $M dv^{\text{con}}$
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

Nonsmooth Newmark’s scheme

The nonsmooth generalized $\alpha$ scheme

Principles

- As usual is the Newmark scheme, the smooth part of the dynamics $Ma \, dt = F(t, q, v) \, dt$ is collocated, i.e.

\[
Ma_{k+1} = F_{k+1} \tag{50}
\]

- the impulsive part a first order approximation is done over the time–step

\[
Mw_{k+1} = G_{k+1} \, P_{k+1} \tag{51}
\]

\[
P_{k+1} \approx \int_{(t_k, t_{k+1})} di \tag{52}
\]
The nonsmooth generalized $\alpha$ scheme

Principles

Given three parameters $\gamma$, $\beta$, $\alpha_m$ and $\alpha_f$ we define

\[
\begin{align*}
Ma_{k+1} - \alpha_m &= F_{k+1} - \alpha_f \\
Mw_{k+1} &= G_{k+1} P_{k+1} \\
v_{k+1} &= v_k + h a_{k+\gamma} + w_{k+1} \\
q_{k+1} &= q_k + hv_k + \frac{h^2}{2} a_{k+2\beta} + \frac{1}{2} hw_{k+1}
\end{align*}
\]

Special cases

- $\alpha_m = \alpha_f = 0$. Nonsmooth Newmark scheme
- $\alpha_m = 0$ and $\alpha_f = \alpha$. Nonsmooth HHT scheme.
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

The nonsmooth generalized $\alpha$ scheme

Example (Two balls oscillator with impact)

$m = 1$ kg

$k = 10^3$ N/m

$q_1$ ..........................................

$q_2$ ..........................................

$m = 1$ kg

$m = 1$ kg
An extension of the Moreau–Jean scheme based on the generalized–\( \alpha \) schemes for the numerical time integration of flexible dynamical systems with contact and friction

The nonsmooth generalized \( \alpha \) scheme

\[
time\text{-step : } h = 2e - 3. \text{ Moreau } (\theta = 1.0). \text{ Newmark } (\gamma = 1.0, \beta = 0.5). \text{ HHT } (\alpha = 0.1)
\]

Position of the first ball

Velocity of the first ball
The nonsmooth generalized $\alpha$ scheme

\begin{align*}
\text{HHT } h &= 10^{-3}, \alpha = 0.1 \\
\text{Moreau time–step } h &= 10^{-5}, \theta = 1.0
\end{align*}
The nonsmooth generalized $\alpha$ scheme

Figure 7. Numerical results for the total energy of the bouncing oscillator.

Figure 8. Comparison the numerical results for the bouncing elastic bar: (a) position, (b) pressure.
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction

Nonsmooth Newmark’s scheme

The nonsmooth generalized $\alpha$ scheme

Figure 2. Examples: (a) bouncing ball; (b) linear vertical oscillator; (c) bouncing of an elastic bar; (d) bouncing of a nonlinear beam pendulum; (e) bouncing of a rigid pendulum

Figure 3 shows the position and velocity of the ball. The errors are computed by comparison with an analytically-exact solution, see Appendix A [15]. Figure 4 shows the convergence analysis of the valid methods. The relative error is analyzed on the $L^1$ norm, which is defined as

$$\parallel e \parallel_1 = \frac{\sum_{i=0}^{N} |e_i|}{\sum_{i=0}^{N} |f(t_i)|}$$

(33)

where $e_i = f_i - f(t_i)$, $f_i$ is the numerical solution and $f(t_i)$ is the exact solution.

The convergence analysis is made on the interval $[0, 4]$ s. As one can see from the figure, all the three methods remain first order accurate in the overall range. However, the nonsmooth generalized-$\alpha$ and the fully implicit Newmark methods have a slightly better accuracy.

5.2. Bouncing of a linear oscillator

In this example, the bouncing of a vertical linear oscillator model is studied, see Figure 2(b). The oscillator consists of two masses connected by a spring. It is subjected to the gravity and has two DOFs in the vertical direction. After the lower mass impacts against the plane, it bounces back with a restitution coefficient of $e = 0.8$. In the meanwhile, it is also subjected to a force by the compressed spring. Thus, a second impact or multiple impacts can occur right after the first impact. In the free-flight mode after impacts, the system is oscillating with its natural frequency. Physical parameters used in this model are as: mass $m = 1$ kg and radius $R = 0.2m$ for each ball; the stiffness of the spring $k = 10^4$ N/m and the unstretched length $l = 1$ m; the initial velocity is zero and the initial height $h_0 = 1.001$ m; the gravity acceleration $g = 10$ m/s$^2$. Copyright © 2012 John Wiley & Sons, Ltd. Int. J. Numer. Meth. Engng (2012) Prepared using nmeauth.cls DOI: 10.1002/nme
The nonsmooth generalized $\alpha$ scheme

Figure 9. Numerical results for the total energy of the bouncing elastic bar
The nonsmooth generalized $\alpha$ scheme

Figure 10. Numerical results for the impact of a flexible rotating beam: (a) position, (b) velocity.
The nonsmooth generalized $\alpha$ scheme

Observed properties on examples

- the scheme is consistent and globally of order one.
- the scheme seems to share the stability property as the original HHT
- the scheme dissipates energy only in high-frequency oscillations (w.r.t the time–step.)

Conclusions & perspectives

- Extension to any multi–step schemes can be done in the same way.
- Improvements of the order by splitting.
- Recast into time–discontinuous Galerkin formulation.
An extension of the Moreau–Jean scheme based on the generalized-\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction

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**Energy Analysis**

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**Time–continuous energy balance equations**

Let us start with the “LTI” Dynamics

\[
\begin{aligned}
M \, dv + (Kq + Cv) \, dt &= F \, dt + di \\
dq &= v^\pm dt
\end{aligned}
\]  

(54)

we get for the Energy Balance

\[
d(v^\top M v) + (v^+ + v^-)(Kq + Cv) \, dt = (v^+ + v^-)F \, dt + (v^+ + v^-) \, di
\]  

(55)

that is

\[
2d\mathcal{E} := d(v^\top M v) + 2q^\top Kdq = 2v^\top F \, dt - 2v^\top Cv \, dt + (v^+ + v^-)^\top di
\]  

(56)

with

\[
\mathcal{E} := \frac{1}{2}v^\top M v + \frac{1}{2}q^\top Kq.
\]  

(57)
An extension of the Moreau–Jean scheme based on the generalized–\(\alpha\) schemes for the numerical time integration of flexible dynamical systems with contact and friction

Energy Analysis

Time–continuous energy balance equations

If we split the differential measure in \(di = \lambda \, dt + \sum_i p_i\delta t_i\), we get

\[
2dE = 2v^\top (F + \lambda) \, dt - 2v^\top Cv \, dt + (v^+ + v^-)^\top p_i\delta t_i \quad \text{(58)}
\]

By integration over a time interval \([t_0, t_1]\) such that \(t_i \in [t_0, t_1]\), we obtain an energy balance equation as

\[
\Delta E := E(t_1) - E(t_0) = \int_{t_0}^{t_1} v^\top F \, dt - \int_{t_0}^{t_1} v^\top Cv \, dt + \int_{t_0}^{t_1} v^\top \lambda \, dt + \frac{1}{2} \sum_i (v^+(t_i) + v^-(t_i))^\top p_i
\]

\(\text{W}^\text{ext}\) \quad \(\text{W}^\text{damping}\) \quad \(\text{W}^\text{con}\) \quad \(\text{W}^\text{impact}\)

\(\text{(59)}\)
Energy analysis

Work performed by the reaction impulse $d_i$

- The term
  \[ W^{\text{con}} = \int_{t_0}^{t_1} v^\top \lambda \, dt \]  
  \[ (60) \]
  is the work done by the contact forces within the time–step. If we consider perfect unilateral constraints, we have $W^{\text{con}} = 0$.

- The term
  \[ W^{\text{impact}} = \frac{1}{2} \sum_i (v^+(t_i) + v^-(t_i))^\top p_i \]  
  \[ (61) \]
  represents the work done by the contact impulse $p_i$ at the time of impact $t_i$. Since $p_i = G(t_i)P_i$ and if we consider the Newton impact law, we have

  \[ W^{\text{impact}} = \frac{1}{2} \sum_i (v^+(t_i) + v^-(t_i))^\top G(t_i)P_i \]
  \[ \frac{1}{2} \sum_i (U^+(t_i) + U^-(t_i))^\top P_i \]
  \[ \frac{1}{2} \sum_i ((1 - e)U^-(t_i))^\top P_i \leq 0 \text{ for } 0 \leq e \leq 1 \]  
  \[ (62) \]
  with the local relative velocity defined as $U(t) = G^\top(t)v(t)$.
Energy analysis for Moreau–Jean scheme

Let us define the discrete approximation of the work done by the external forces within the step by

$$W_{k+1}^{\text{ext}} = h v_{k+\theta}^T F_{k+\theta} \approx \int_{t_k}^{t_{k+1}} F v \, dt,$$

(63)

and the discrete approximation of the work done by the damping term by

$$W_{k+1}^{\text{damping}} = -h v_{k+\theta}^T C v_{k+\theta} \approx -\int_{t_k}^{t_{k+1}} v^T C v \, dt.$$

(64)

Lemma

The variation of the total mechanical energy over a time-step $[t_k, t_{k+1}]$ performed by the Moreau–Jean scheme (27) is

$$\Delta E - W_{k+1}^{\text{ext}} - W_{k+1}^{\text{damping}} = \left( \frac{1}{2} - \theta \right) \left[ \| v_{k+1} - v_k \|_M^2 + \| (q_{k+1} - q_k) \|_K^2 \right] + U_{k+\theta}^T P_{k+1}$$

(65)
Energy analysis for Moreau–Jean scheme

Proposition

The Moreau–Jean scheme dissipates energy in the sense that

\[ \mathcal{E}(t_{k+1}) - \mathcal{E}(t_k) \leq W_{k+1}^{\text{ext}} + W_{k+1}^{\text{damping}}, \]

if

\[ \frac{1}{2} \leq \theta \leq \frac{1}{1 + e} \leq 1. \]

where \( e = \max \alpha^\alpha, \alpha \in \mathcal{I} \). In particular, for \( e = 0 \), we get \( \frac{1}{2} \leq \theta \leq 1 \) and or \( e = 1 \), we get \( \theta = \frac{1}{2} \).
Energy analysis for Moreau–Jean scheme

Variant of the Moreau scheme that always dissipates energy

Let us consider the variant of the Moreau scheme

\[
\begin{align*}
M(v_{k+1} - v_k) + hKq_{k+\theta} - hF_{k+\theta} &= p_{k+1} = GP_{k+1}, \quad (68a) \\
q_{k+1} &= q_k + hv_{k+1/2}, \quad (68b) \\
U_{k+1} &= G^\top v_{k+1} \quad (68c) \\
\text{if } \bar{g}^\alpha_{k+1} \leq 0 \text{ then } 0 &\leq U^\alpha_{k+1} + eU^\alpha_k \perp P^\alpha_{k+1} \geq 0, \quad \alpha \in \mathcal{I} \quad (68d) \\
\text{otherwise } P^\alpha_{k+1} &= 0.
\end{align*}
\]
Lemma

The variation of the total mechanical energy performed by the scheme (68) over a time-step is

\[ \Delta \mathcal{E} - \tilde{W}_{k+1}^{\text{ext}} - W_{k+1}^{\text{damping}} = \left( \frac{1}{2} - \theta \right) \| (q_{k+1} - q_k) \|^2_K + U_{k+1/2}^\top P_{k+1} \]  

(69)

If \( \theta \geq 1/2 \), then the scheme (68) dissipates energy in the sense that

\[ \mathcal{E}(t_{k+1}) - \mathcal{E}(t_k) \leq \tilde{W}_{k+1}^{\text{ext}} + W_{k+1}^{\text{damping}}. \]  

(70)
Energy analysis for nonsmooth Newmark scheme

Let us define the discrete approximation of the work done by the external forces within the step by

\[ W_{ext}^{k+1} = (q_{k+1} - q_k)^\top F_{k+\gamma} \approx \int_{t_k}^{t_{k+1}} F v \, dt \tag{71} \]

and the discrete approximation of the work done by the damping term by

\[ W_{damping}^{k+1} = -(q_{k+1} - q_k)^\top C v_{k+\gamma} \approx -\int_{t_k}^{t_{k+1}} v^\top C v \, dt. \tag{72} \]

Lemma

The variation of energy over a time–step performed by the scheme is

\[
\Delta E - W_{ext}^{k+1} - W_{damping}^{k+1} = \left( \frac{1}{2} - \gamma \right) \left\| (q_{k+1} - q_k)^2 \right\|_K + P_{k+1}^{\top} U_{k+1/2} \\
+ \frac{h}{2} (2\beta - \gamma) \left[ (q_{k+1} - q_k)^\top K (v_{k+1} - v_k) + \left\| (v_{k+1} - v_k) \right\|_C^2 \right] \\
- \frac{h}{2} (2\beta - \gamma) \left[ (v_{k+1} - v_k)^\top (F_{k+1} - F_k) - (a_{k+1} - a_k)^\top GP_{k+1} \right]. 
\] 

\tag{73}
An extension of the Moreau–Jean scheme based on the generalized–$\alpha$ schemes for the numerical time integration of flexible dynamical systems with contact and friction.

**Energy Analysis**

Energy Analysis for the nonsmooth Newmark scheme

**Energy analysis for Newmark’s scheme**

Define an discrete “algorithmic energy” (discrete storage function) of the form

$$K(q, v, a) = \mathcal{E}(q, v) + \frac{h^2}{4} (2\beta - \gamma) a^\top M a.$$  \hspace{1cm} (74)

**Proposition**

The variation of the “algorithmic” energy $\Delta K$ over a time–step performed by the nonsmooth Newmark scheme is

$$\Delta K - W^\text{ext}_{k+1} - W^\text{damping}_{k+1} = \left( \frac{1}{2} - \gamma \right) \left[ \| q_{k+1} - q_k \|_K^2 + \frac{h}{2} (2\beta - \gamma) \| a_{k+1} - a_k \|_M^2 \right]$$

$$+ U^\top_{k+1/2} P_{k+1}.$$ \hspace{1cm} (75)

Moreover, the nonsmooth Newmark scheme dissipates the “algorithmic” energy $K$ in the following sense

$$\Delta K - W^\text{ext}_{k+1} - W^\text{damping}_{k+1} \leq 0,$$  \hspace{1cm} (76)

for

$$2\beta \geq \gamma \geq \frac{1}{2}.$$  \hspace{1cm} (77)
Energy analysis for HHT scheme

Augmented dynamics

Let us introduce the modified dynamics

\[ Ma(t) + Cv(t) + Kq(t) = F(t) + \frac{\alpha}{\nu} [Kw(t) + Cx(t) - y(t)] \]  \hfill (78)

and the following auxiliary dynamics that filter the previous one

\[ \nu h \dot{w}(t) + w(t) = \nu h \dot{q}(t) \]
\[ \nu h \dot{x}(t) + x(t) = \nu h \dot{v}(t) \]
\[ \nu h \dot{y}(t) + y(t) = \nu h \dot{F}(t) \]  \hfill (79)
Energy analysis for HHT scheme

Discretized Augmented dynamics

The equation (79) are discretized as follows

\[
\begin{align*}
\nu(w_{k+1} - w_k) + \frac{1}{2}(w_{k+1} + w_k) &= \nu(q_{k+1} - q_k) \\
\nu(x_{k+1} - x_k) + \frac{1}{2}(x_{k+1} + x_k) &= \nu(v_{k+1} - v_k) \\
\nu(y_{k+1} - y_k) + \frac{1}{2}(y_{k+1} + y_k) &= \nu(F_{k+1} - F_k)
\end{align*}
\] (80)

or rearranging the terms

\[
\begin{align*}
\left(\frac{1}{2} + \nu\right)w_{k+1} + \left(\frac{1}{2} - \nu\right)w_k &= \nu(q_{k+1} - q_k) \\
\left(\frac{1}{2} + \nu\right)x_{k+1} + \left(\frac{1}{2} - \nu\right)x_k &= \nu(v_{k+1} - v_k) \\
\left(\frac{1}{2} + \nu\right)y_{k+1} + \left(\frac{1}{2} - \nu\right)y_k &= \nu(F_{k+1} - F_k)
\end{align*}
\] (81)

With the special choice \(\nu = \frac{1}{2}\), we obtain the HHT scheme collocation that is

\[
Ma_{k+1} + (1 - \alpha)[Kq_{k+1} + Cv_{k+1}] + \alpha[Kq_k + Cv_k] = (1 - \alpha)F_{k+1} + \alpha F_k
\] (82)
Define an discrete “algorithmic energy” (discrete storage function) of the form

$$\mathcal{H}(q, v, a, w) = \mathcal{E}(q, v) + \frac{h^2}{4}(2\beta - \gamma)a^\top Ma + 2\alpha(1 - \gamma)w^\top Kw.$$  \hspace{1cm} (83)

Let us define the approximation of works as follows:

$$W_{k+1}^{\text{ext}} = (q_{k+1} - q_k)^\top [(1 - \alpha)F_{k,\gamma} + \alpha F_{k-1,\gamma}] \approx \int_{t_k}^{t_{k+1}} Fv \, dt$$ \hspace{1cm} (84)

and

$$W_{k+1}^{\text{damping}} = -(q_{k+1} - q_k)^\top C [(1 - \alpha)v_{k,\gamma} + \alpha v_{k-1,\gamma}] \approx -\int_{t_k}^{t_{k+1}} v^\top Cv \, dt.$$ \hspace{1cm} (85)
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction

Energy Analysis

Energy Analysis for the nonsmooth Newmark scheme

Energy analysis for nonsmooth HHT scheme

Proposition

The variation of the “algorithmic” energy $\Delta H$ over a time–step performed by the nonsmooth HHT scheme is

$$
\Delta H - W_{k+1}^{\text{ext}} - W_{k+1}^{\text{damping}} = U_{k+1/2}^T P_{k+1} - \frac{1}{2} h^2 (\gamma - \frac{1}{2})(2\beta - \gamma) \|(a_{k+1} - a_k)\|^2_M
- (\gamma - \frac{1}{2} - \alpha)\|q_{k+1} - q_k\|^2_K - 2\alpha (1 - \gamma)\|z_{k+1} - z_k\|^2_K.
$$

Moreover, the nonsmooth HHT scheme dissipates the “algorithmic” energy $H$ in the following sense

$$
\Delta H - W_{k+1}^{\text{ext}} - W_{k+1}^{\text{damping}} \leq 0,
$$

if

$$
2\beta \geq \gamma \geq \frac{1}{2} \quad \text{and} \quad 0 \leq \alpha \leq \gamma - \frac{1}{2} \leq \frac{1}{2}.
$$
Energy analysis for nonsmooth schemes

Conclusions

▶ For the Moreau–Jean, a simple variant allows us to obtain a scheme which always dissipates energy.

▶ For the Newmark and the HHT scheme with retrieve the dissipation properties as the smooth case. The term associated with impact is added is the balance.

▶ For the generalized–α, similar analysis can be performed but some issues in the interpretation of results. New variant of the generalized–α scheme has been proposed.

▶ Open Problem: We get dissipation inequality for discrete with quadratic storage function and plausible supply rate. The rest step is to conclude to the stability of the scheme with this argument. At least, we can bound discrete variable and conclude to the convergence of the scheme.
Objectives & Motivations

- Problem setting
- Measures Decomposition

The Moreau’s sweeping process

- State-of-the-art

Background

- Newmark’s scheme.
- HHT scheme
- Generalized $\alpha$-methods

Newmark’s scheme and the $\alpha$–methods family

Nonsmooth Newmark’s scheme

- Time-continuous energy balance equations
- Energy analysis for Moreau–Jean scheme
- Energy Analysis for the nonsmooth Newmark scheme

Energy Analysis

- The impacting beam benchmark

Discussion and FEM applications
Impact in flexible structure

Example (The impacting bar)
Impact in flexible structure

Brief Literature

- (Hughes et al., 1976) Impact of two elastic bars. Standard Newmark in position and specific release and contact
- (Laursen and Love, 2002, 2003) Implicit treatment of contact reaction with a position level constraints
- (Chawla and Laursen, 1998; Laursen and Chawla, 1997) Implicit treatment of contact reaction with a pseudo velocity level constraints (algorithmic gap rate)
- (Vola et al., 1998) Comparison of Moreau–Jean scheme and standard Newmark scheme
- (Dumont and Paoli, 2006) Central–difference scheme with
- (Deuflhard et al., 2007) Contact stabilized Newmark scheme. Position level Newmark scheme with pre-projection of the velocity.
- (Doyen et al., 2011) Comparison of various position level schemes.

Although artifacts and oscillations are commonly observed, the question of nonsmoothness of the solution, the velocity based formulation and then a possible impact law in never addressed.
Impact in flexible structure

Position based constraints

1000 nodes. $v_0 = -0.1$. $h = 5 \times 10^{-5}$ Nonsmooth Newmark scheme $\gamma = 0.6, \beta = \gamma/2$

index 3 DAE problem: oscillations at the velocity level. $\Rightarrow$ reduce the index.
Impact in flexible structure

Influence of high frequencies dissipation

1000 nodes. \( v_0 = -0.1 \). \( h = 5.10^{-6} \) \( e = 0.0 \) Nonsmooth Newmark scheme
\( \gamma = 0.5, \beta = \gamma/2. \)
Impact in flexible structure

Influence of high frequencies dissipation

1000 nodes. $v_0 = -0.1$. $h = 5.10^{-6}$, $e = 0.0$ Nonsmooth Newmark scheme
$\gamma = 0.6$, $\beta = \gamma/2$. 

---

Discussion and FEM applications
Impact in flexible structure

Influence of mesh discretization

1000 nodes. $v_0 = -0.1$. $h = 5 \times 10^{-6}$ e = 0.0 Nonsmooth Newmark scheme $\gamma = 0.6, \beta = \gamma/2$. 

![Graph showing bar contact point position, velocity, and reaction force over time.](image)
Impact in flexible structure

Influence of mesh discretization

100 nodes.  $v_0 = -0.1$.  $h = 5 \times 10^{-6}$  $e = 0.0$ Nonsmooth Newmark scheme

$\gamma = 0.6$, $\beta = \gamma / 2$. 

![Graph showing bar contact point position, velocity, and reaction force over time.](image-url)
Impact in flexible structure

Influence of mesh discretization
10 nodes. $v_0 = -0.1$. $h = 5.10^{-6}$ $e = 0.0$ Nonsmooth Newmark scheme $\gamma = 0.6$, $\beta = \gamma/2$. 

![Graph showing bar contact point position, velocity, and reaction force over time.](image)
Impact in flexible structure

**Influence of time-step**

1000 nodes. $v_0 = -0.1$. $h = 5.10^{-6}$ $e = 0.0$ Nonsmooth Newmark scheme $\gamma = 0.6$, $\beta = \gamma/2$. 

![Graph showing bar contact point position, velocity, and reaction force over time]
Impact in flexible structure

Influence of time-step

1000 nodes. $v_0 = -0.1$. $h = 5 \times 10^{-5}$ $e = 0.0$ Nonsmooth Newmark scheme
$\gamma = 0.6$, $\beta = \gamma/2$. 
Impact in flexible structure

Influence of time-step

1000 nodes. $v_0 = -0.1$. $h = 5.10^{-4}$ e = 0.0 Nonsmooth Newmark scheme
$\gamma = 0.6$, $\beta = \gamma/2$. 

Discussion and FEM applications – 70/74
Impact in flexible structure

Influence of the coefficient of restitution

1000 nodes. $v_0 = -0.1$. $h = 5 \times 10^{-5}$ $e = 0.0$ Nonsmooth Newmark scheme
$
\gamma = 0.6, \beta = \gamma / 2.
$
Impact in flexible structure

Influence of the coefficient of restitution

1000 nodes. $v_0 = -0.1$. $h = 5 \times 10^{-5}$ $e = 0.5$ Nonsmooth Newmark scheme

$\gamma = 0.6$, $\beta = \gamma/2$. 
An extension of the Moreau–Jean scheme based on the generalized-α schemes for the numerical time integration of flexible dynamical systems with contact and friction

Discussion and FEM applications

The impacting beam benchmark

Impact in flexible structure

Influence of the coefficient of restitution

1000 nodes. \( v_0 = -0.1 \). \( h = 5 \times 10^{-5} \). \( e = 1.0 \). Nonsmooth Newmark scheme \( \gamma = 0.6 \), \( \beta = \gamma/2 \).
Impact in flexible structure

Discussion

- Reduction of order needs to write the constraints at the velocity level. Even in GGL approach.

- How to known if we need an impact law? For a finite–freedom mechanical systems, we have to precise one. At the limit, the concept of coefficient of restitution can be a problem. Work of Michelle Schatzman.
Thank you for your attention.
Objectives & Motivations
  Problem setting
  Measures Decomposition

The Moreau’s sweeping process
  State–of–the–art

Background
  Newmark’s scheme.
  HHT scheme
  Generalized $\alpha$–methods

Newmark’s scheme and the $\alpha$–methods family

Nonsmooth Newmark’s scheme
  Time–continuous energy balance equations
  Energy analysis for Moreau–Jean scheme
  Energy Analysis for the nonsmooth Newmark scheme

Energy Analysis
  The impacting beam benchmark

Discussion and FEM applications
An extension of the Moreau–Jean scheme based on the generalized–α schemes for the numerical time integration of flexible dynamical systems with contact and friction.

References


An extension of the Moreau–Jean scheme based on the generalized–\( \alpha \) schemes for the numerical time integration of flexible dynamical systems with contact and friction.

References


Discussion and FEM applications
The impacting beam benchmark


