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## NUMERICAL INVESTIGATION OF A PLAIN STRAIN STATE FOR A BODY WITH THIN COVER USING DOMAIN DECOMPOSITION

IVAN DYKAK, YAREMA SAVULA, ANDRIY STYANAR

**РЕЗЮМЕ.** Розглядається модель, яка описує напружено деформований стан двовимірного гетерогенного тіла з тонким покриттям. Спочатку доведено збіжність ітеративного алгоритму, побудованого на основі поєднання методу скінченних елементів (МСЕ) та методу граничних елементів (МГЕ) з використанням декомпозиції областей. Після цього алгоритм проілюстровано на прикладі двовимірної задачі для тіла з покриттям.

**ABSTRACT.** We consider a model, that describes the plain stress state of the  $2D$  heterogeneous elastic body with the thin cover. First we prove the convergence of the iterative algorithm based on finite element method/boundary element method (FEM/BEM) coupling using domain decomposition. Further we illustrate this algorithm with an example of  $2D$  problem for the body with a cover.

### 1. INTRODUCTION

A lot of structures, both natural and artificial, contain thin covers or thin inclusions. Therefore, the problem of analyzing the stress-strain state of such bodies is of great importance. Typically they consist of two or more homogeneous parts that have a big differences in physical dimensions and properties between them. A lot of aspects of the problems, related to this subject, were analyzed (see for example [2, 4, 5, 7, 8]). In this paper we use the combined model, where the parts of the body with comparable physical dimensions are described by the linear elasticity equations, whereas the stress state of the thin cover is described by Timoshenko shell theory equations [5]. These parts are connected using the appropriate coupling conditions on the common boundaries.

In order to perform numerical analysis of our model we solve the corresponding problems in thin shells by finite element method (FEM) with bubble basis functions, and the other parts of the body are solved numerically using boundary element method (BEM) with linear basis functions; the iterative domain decomposition algorithm is then used to connect the solutions in both domains.

In this paper we also prove the properties of our model and prove the convergence of the algorithm.

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<sup>†</sup>*Key words.* Elasticity theory, boundary element method, finite element method, domain decomposition.

## 2. PROBLEM STATEMENT

Let us consider a problem of plane strain of cylindrical body  $\Omega_1$  with the cover  $\Omega_2$ .

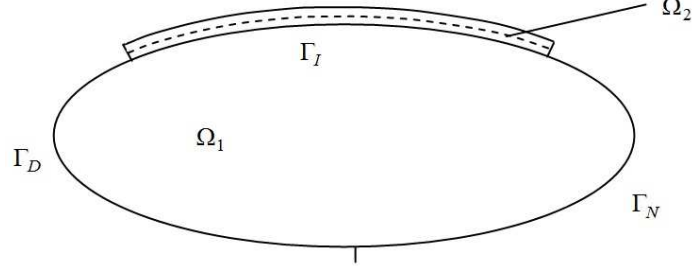


FIG. 1. Body with cover

The plane strain stress of the body in  $\Omega_1$  can be described by [1]

$$\begin{aligned} \frac{\partial \sigma_{11}}{\partial x_1} + \frac{\partial \sigma_{12}}{\partial x_2} &= f_1, \\ \frac{\partial \sigma_{21}}{\partial x_1} + \frac{\partial \sigma_{22}}{\partial x_2} &= f_2 \end{aligned} \tag{1}$$

that holds for  $x \in \Omega_1$ ,  $x = x_1, x_2$ . Here  $f = f_1, f_2$  denotes the volume forces that act on the body in  $\Omega_1$ . From the Hook's law it follows that the components of the stress tensor can be written as

$$\sigma_{ij} = \frac{1}{2} E_1 \left( \frac{\partial u_i}{\partial x_j} + \frac{\partial u_j}{\partial x_i} \right), \quad i, j = 1, 2,$$

where  $u(x) = u_1(x), u_2(x)$  is the displacement vector with  $u_i$  being the displacements in the directions  $x_i$  for  $i = 1, 2$ ;  $E_1$  is the Young's modulus of the body in  $\Omega_1$ . In the following we assume that no volume forces act on the body in  $\Omega_1$ .

Let us denote by  $n$  the outer normal vector to  $\Omega_1$ , and by  $\tau$  – the tangent vector. Equations (1) are considered together with the boundary conditions

$$u_v = 0, \quad u_\tau = 0, \quad x \in \Gamma_D$$

and

$$\sigma_{vv} = 0, \quad \sigma_{v\tau} = 0, \quad x \in \Gamma_N,$$

where  $u_v$  and  $u_\tau$  are the components of the displacement vector in the coordinate system  $n, \tau$ . Similarly,  $\sigma_{vv}$  and  $\sigma_{v\tau}$  are the components of the stress tensor in the  $n, \tau$  coordinate system.

For the description of the cover in  $\Omega_2$  we use the equations of Timoshenko shell theory for the cylindrical shell of the form [5]

$$\begin{aligned}
 -\frac{1}{A_1} \frac{dT_{11}}{d\xi_1} - k_1 T_{13} &= p_1, \\
 -\frac{1}{A_1} \frac{dT_{13}}{d\xi_1} + k_1 T_{11} &= p_3, \\
 -\frac{1}{A_1} \frac{dM_{11}}{d\xi_1} + T_{13} &= m_1, \quad -1 \leq \xi_1 \leq 0,
 \end{aligned} \tag{2}$$

where  $v_1$ ,  $w$ ,  $\gamma_1$  are the displacements and angle of revolution in the shell;  $T_{11}$ ,  $T_{13}$ ,  $M_{11}$  are the forces and moments in the shell;  $A_1 = A_1(\xi_1)$ ,  $k_1 = k_1(\xi_1)$  correspond to Lamé parameter and median surface curvature parameter;  $p_1$ ,  $p_3$ ,  $m_1$  are given functions; it holds

$$T_{11} = \frac{E_2 h}{1 - v_2^2} \varepsilon_{11}, \quad T_{13} = k' G' h \varepsilon_{13}, \quad M_{11} = \frac{E_2 h^3}{12(1 - v_2^2)} \chi_{11}, \tag{3}$$

$$\varepsilon_{11} = \frac{1}{A_1} \frac{dv_1}{d\xi_1} + k_1 w, \quad \varepsilon_{13} = \frac{1}{A_1} \frac{dw}{d\xi_1} + \gamma_1 - k_1 v_1, \quad \chi_{11} = \frac{1}{A_1} \frac{d\gamma_1}{d\xi_1}, \tag{4}$$

$$\begin{aligned}
 p_1 &= \left(1 + k_1 \frac{h}{2}\right) \sigma_{13}^+ - \left(1 - k_1 \frac{h}{2}\right) \sigma_{13}^-, \\
 p_3 &= \left(1 + k_1 \frac{h}{2}\right) \sigma_{33}^+ - \left(1 - k_1 \frac{h}{2}\right) \sigma_{33}^-,
 \end{aligned} \tag{5}$$

$$m_1 = \frac{h}{2} \left( \left(1 + k_1 \frac{h}{2}\right) \sigma_{13}^+ - \left(1 - k_1 \frac{h}{2}\right) \sigma_{13}^- \right).$$

Here  $E_2$  is the Young's modulus for the shell,  $v_2$  is the Poisson's ratio;  $g_1, g_3$  are the components of the volume forces vector, that act on the shell;  $\sigma_{ij}^+, \sigma_{ij}^-$ ,  $i, j = 1, 3$  are the components of the stress tensor on the outer ( $\xi_3 = \frac{h}{2}$ ) and inner ( $\xi_3 = -\frac{h}{2}$ ) surfaces of the shell. It is known, that in the case of isotropic bodies we have  $k' = \frac{5}{6}$ ,  $G' = \frac{E_2}{2(1+v_2)}$ .

At each end of the thin cover we impose boundary conditions either on the displacements  $v_1$ ,  $w$  and  $\gamma_1$  or on the forces  $T_{11}$ ,  $T_{13}$  and moment  $M_{11}$  in the shell (if the end is subjected to load or free). At the outer surface of the shell we prescribe to  $\sigma_{13}^+$  and  $\sigma_{33}^+$  some given stresses.

**Remark 1.** *The choice of 2D curvilinear coordinate system for the shell as  $\xi_1, \xi_3$  (instead of  $\xi_1, \xi_2$ ) is based on the fact, that 2D problem is obtained from the 3D case by assuming the cylinder being infinite in the direction of  $\xi_2$ .*

*On the boundary  $\Gamma_I$ , common to both  $\Omega_1$  and  $\Omega_2$  we prescribe the following coupling conditions [5]:*

$$u_v = w, \quad u_\tau = v_1 - \frac{h}{2}\gamma_1, \quad (6)$$

$$\sigma_{vv} = \sigma_{33}^-, \quad \sigma_{v\tau} = \sigma_{13}^-.$$

Let us rewrite the coupling conditions (6) on  $\Gamma_I$  as follows:

$$\begin{aligned} u_v = w, \quad u_\tau = v_1 - \frac{h}{2}\gamma_1, \\ A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{vv} - A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{33}^- = 0, \\ A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{v\tau} - A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{13}^- = 0. \end{aligned} \quad (7)$$

### 3. THE PROPERTIES OF THE STEKLOV-POINCARÉ OPERATORS AND CONVERGENCE OF THE DOMAIN DECOMPOSITION ITERATIVE ALGORITHM

Let us suppose that on the interface  $\Gamma_I$  the displacement is equal to  $\varphi = \varphi_1, \varphi_2, \varphi_i \in H^1(\Gamma_I), i = 1, 2$ . In the following we consider the Steklov-Poincaré operator  $S$  for our problem as well as local Steklov-Poincaré operators  $S_i$ , that correspond to  $\Omega_i, i = 1, 2$ . Therefore, we have from (7)

$$\langle S\varphi, \psi \rangle_{\Gamma_I} = \langle S_1\varphi, \psi \rangle_{\Gamma_I} + \langle S_2\varphi, \psi \rangle_{\Gamma_I}, \quad \forall \varphi, \psi \in H^1(\Gamma_I) \times H^1(\Gamma_I)$$

$$\begin{aligned} \langle S_1\varphi, \psi \rangle_{\Gamma_I} = & \left\langle A_1 \left(1 - k_1 \frac{h}{2}\right) G_I \sigma_{vv}(\varphi), \psi_1 \right\rangle_{\Gamma_I} + \\ & + \left\langle A_1 \left(1 - k_1 \frac{h}{2}\right) G_I \sigma_{v\tau}(\varphi), \psi_2 \right\rangle_{\Gamma_I}, \end{aligned} \quad (8)$$

$$\begin{aligned} \langle S_2\varphi, \psi \rangle_{\Gamma_I} = & \left\langle -A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{33}^-(\varphi), \psi_1 \right\rangle_{\Gamma_I} + \\ & + \left\langle A_1 \left(1 - k_1 \frac{h}{2}\right) \sigma_{13}^-(\varphi), \psi_2 \right\rangle_{\Gamma_I}, \end{aligned}$$

where  $G_I\sigma$  is the trace of  $\sigma$  on  $\Gamma_I$ ;  $\langle u, v \rangle_{\Gamma_I}$  denotes the bilinear form which formally can be written as

$$\langle u, v \rangle_{\Gamma_I} = \int_{\Gamma_I} uv d\Gamma_I.$$

First we prove that there exists a unique solution to the problem for Steklov-Poincaré operators. For this purpose we will use the Lax-Milgram lemma.

Let  $\Omega_2^*$  be a midline of  $\Omega_2$ . Without loss of generality we assume that  $g_1 = g_3 = \sigma_{13}^+ = \sigma_{33}^+ = 0$ . Moreover, one notices that all the displacements defined

in  $\Omega_2$  are continuous with respect to  $\xi_3$ , since both equations and boundary conditions are independent of  $\xi_3$ . Using the coupling conditions (7), one can rewrite (8) as

$$\begin{aligned}
 \langle S_2 \varphi, \psi \rangle_{\Gamma_I} &= \left\langle -A_1 \left( 1 - k_1 \frac{h}{2} \right) \sigma_{33}^-(\varphi), \tilde{w} \right\rangle_{\Gamma_I} + \\
 &+ \left\langle -A_1 \left( 1 - k_1 \frac{h}{2} \right) \sigma_{13}^-(\varphi), \left( \tilde{v}_1 - \frac{h}{2} \tilde{\gamma}_1 \right) \right\rangle_{\Gamma_I} = \\
 &= \left( -A_1 \left( 1 - k_1 \frac{h}{2} \right) \sigma_{33}^-, \tilde{w} \right)_{\Omega_2^*} + \left( -A_1 \left( 1 - k_1 \frac{h}{2} \right) \sigma_{13}^-, \tilde{v}_1 \right)_{\Omega_2^*} + \\
 &+ \left( A_1 \frac{h}{2} \left( 1 - k_1 \frac{h}{2} \right) \sigma_{13}^-, \tilde{\gamma}_1 \right)_{\Omega_2^*}, \tag{9}
 \end{aligned}$$

where

$$(u, v)_{\Omega_2^*} = \int_{\Omega_2^*} uv \, d\Omega_2^*.$$

Let us substitute into (9) the corresponding left sides of the system of equations (2)-(5):

$$\begin{aligned}
 \langle S_2 \varphi, \psi \rangle_{\Gamma_I} &= \left( -\frac{dT_{13}}{d\xi_1} + k_1 A_1 T_{11}, \tilde{w} \right)_{\Omega_2^*} + \\
 &+ \left( -\frac{dT_{11}}{d\xi_1} - k_1 A_1 T_{13}, \tilde{v}_1 \right)_{\Omega_2^*} + \left( -\frac{dM_{11}}{d\xi_1} + A_1 T_{13}, \tilde{\gamma}_1 \right)_{\Omega_2^*}.
 \end{aligned}$$

After integrating by parts one can easily notice that the coerciveness and symmetry of the Steklov-Poincaré operator  $S_2$  follows from the properties of the corresponding operator defined on the midline  $\Omega_2^*$  which has been proven in [2]. Therefore, one obtains

$$\begin{aligned}
 \langle S_2 \varphi, \varphi \rangle_{\Gamma_I} &\geq c^2 \int_{-1}^0 \left( \left( \frac{dv_1}{d\xi_1} \right)^2 + \left( \frac{dw}{d\xi_1} \right)^2 + \left( \frac{d\gamma_1}{d\xi_1} \right)^2 \right) d\Omega_2^* + \\
 &+ c^2 \int_{-1}^0 (v_1^2 + w^2 + \gamma_1^2) d\Omega_2^*, \quad c \neq 0.
 \end{aligned}$$

Further,

$$\langle S_2 \varphi, \varphi \rangle_{\Gamma_I} \geq c_1^2 \int_{-1}^0 \left( \left( \frac{dw}{d\xi_1} \right)^2 + \left( \frac{dv_1}{d\xi_1} - \frac{h}{2} \frac{d\gamma_1}{d\xi_1} \right)^2 \right) d\Omega_2^* +$$

$$+c_1^2 \int_{-1}^0 \left( w^2 + \left( v_1 - \frac{h}{2} \gamma_1 \right)^2 \right) d\Omega_2^*, \quad c_1 \neq 0.$$

Thus,  $S_2$  is coercive. The linearity of  $S_2$  follows directly from the linearity of the corresponding operator in  $\Omega_2^*$ .

Let us now prove the continuity of  $S_2$ . For this purpose, firstly one proves the continuity of the following operator in  $\Omega_2^*$

$$(Ay, \tilde{y})_{\Omega_2^*} = \left( -\frac{dT_{13}}{d\xi_1} + k_1 A_1 T_{11}, \tilde{w} \right)_{\Omega_2^*} + \left( -\frac{dT_{11}}{d\xi_1} - k_1 A_1 T_{13}, \tilde{v}_1 \right)_{\Omega_2^*} + \left( -\frac{dM_{11}}{d\xi_1} + A_1 T_{13}, \tilde{\gamma}_1 \right)_{\Omega_2^*},$$

where  $y = v_1, w, \gamma_1$ ,  $\tilde{y} = \tilde{v}_1, \tilde{w}, \tilde{\gamma}_1$ . Using Cauchy-Schwarz inequality, one obtains for  $y, \tilde{y} \in H^1(\Gamma_I) \times H^1(\Gamma_I) \times H^1(\Gamma_I)$

$$\begin{aligned} (Ay, \tilde{y})_{\Omega_2^*} &= \int_{-1}^0 \left( T_{13} \frac{d\tilde{w}}{d\xi_1} + k_1 A_1 T_{11} \tilde{w} \right) d\xi_1 + \\ &+ \int_{-1}^0 \left( T_{11} \frac{d\tilde{v}_1}{d\xi_1} - k_1 A_1 T_{13} \tilde{v}_1 \right) d\xi_1 + \int_{-1}^0 \left( M_{11} \frac{d\tilde{\gamma}_1}{d\xi_1} + A_1 T_{13} \tilde{\gamma}_1 \right) d\xi_1 = \\ &= \int_{-1}^0 \left( k' G' h \left( \frac{1}{A_1} \frac{dw}{d\xi_1} + \gamma_1 - k_1 v_1 \right) \frac{d\tilde{w}}{d\xi_1} + \right. \\ &+ k_1 A_1 \frac{E_2 h}{1 - v_2^2} \left( \frac{1}{A_1} \frac{dv_1}{d\xi_1} + k_1 w \right) \tilde{w} \Big) d\xi_1 + \\ &+ \int_{-1}^0 \left( \frac{E_2 h}{1 - v_2^2} \left( \frac{1}{A_1} \frac{dv_1}{d\xi_1} + k_1 w \right) \frac{d\tilde{v}_1}{d\xi_1} - \right. \\ &\left. - k_1 A_1 k' G' h \left( \frac{1}{A_1} \frac{dw}{d\xi_1} + \gamma_1 - k_1 v_1 \right) \tilde{v}_1 \right) d\xi_1 + \\ &+ \int_{-1}^0 \left( \frac{E_2 h^3}{12(1 - v_2^2)} \frac{1}{A_1} \frac{d\gamma_1}{d\xi_1} \frac{d\tilde{\gamma}_1}{d\xi_1} + A_1 k' G' h \left( \frac{1}{A_1} \frac{dw}{d\xi_1} + \gamma_1 - k_1 v_1 \right) \tilde{\gamma}_1 \right) d\xi_1 \leq \\ &\leq k' G' h \frac{1}{A_1^m} \left[ \int_{-1}^0 \left( \frac{dw}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{w}}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} + \end{aligned}$$

$$\begin{aligned}
 & +k'G'h \left[ \int_{-1}^0 (\gamma_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{w}}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & +k'G'h |k_1^M| \left[ \int_{-1}^0 (v_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{w}}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + \frac{E_2 h}{1 - v_2^2} |k_1^M| \left[ \int_{-1}^0 \left( \frac{dv_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{w})^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + (A_1 |k_1|)^M \frac{E_2 h}{1 - v_2^2} \left[ \int_{-1}^0 (w)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{w})^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + \frac{E_2 h}{1 - v_2^2} \frac{1}{A_1^m} \left[ \int_{-1}^0 \left( \frac{dv_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{v}_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + \frac{E_2 h}{1 - v_2^2} |k_1^M| \left[ \int_{-1}^0 (w)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{v}_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + \frac{E_2 h}{1 - v_2^2} |k_1^M| \left[ \int_{-1}^0 \left( \frac{dw}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{v}_1)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + k'G'h (A_1 |k_1|)^M \left[ \int_{-1}^0 (\gamma_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{v}_1)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + k'G'h (A_1 k_1^2)^M \left[ \int_{-1}^0 (v_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{v}_1)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
 & + \frac{E_2 h^3}{12 (1 - v_2^2)} \frac{1}{A_1^m} \left[ \int_{-1}^0 \left( \frac{d\gamma_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 \left( \frac{d\tilde{\gamma}_1}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} +
 \end{aligned}$$

$$\begin{aligned}
& +k'G'h \left[ \int_{-1}^0 \left( \frac{dw}{d\xi_1} \right)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{\gamma}_1)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
& +k'G'hA_1^M \left[ \int_{-1}^0 (\gamma_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{\gamma}_1)^2 d\xi_1 \right]^{\frac{1}{2}} + \\
& +k'G'h(A_1|k_1|)^M \left[ \int_{-1}^0 (v_1)^2 d\xi_1 \right]^{\frac{1}{2}} \left[ \int_{-1}^0 (\tilde{\gamma}_1)^2 d\xi_1 \right]^{\frac{1}{2}} \leq \\
& \leq C^2 \|y\|_{H^1(\Omega_2^*)} \|\tilde{y}\|_{H^1(\Omega_2^*)}, \quad C \neq 0.
\end{aligned}$$

In the above  $f^M = \sup_{\Omega_2^*} f$ ,  $f^m = \inf_{\Omega_2^*} f$ . As a result, the continuity of the operator  $A$  is proven. Taking into account the continuity of the operator  $A$ , we can conclude

$$\begin{aligned}
& \langle S_2\varphi, \psi \rangle_{\Gamma_I} \leq \\
& \leq C^2 \left[ \int_{-1}^0 \left( \left( \frac{dv_1}{d\xi_1} \right)^2 + \left( \frac{dw}{d\xi_1} \right)^2 + \left( \frac{d\gamma_1}{d\xi_1} \right)^2 + v_1^2 + w^2 + \gamma_1^2 \right) d\Omega_2^* \right]^{\frac{1}{2}} \times \\
& \times \left[ \int_{-1}^0 \left( \left( \frac{d\tilde{v}_1}{d\xi_1} \right)^2 + \left( \frac{d\tilde{w}}{d\xi_1} \right)^2 + \left( \frac{d\tilde{\gamma}_1}{d\xi_1} \right)^2 + \tilde{v}_1^2 + \tilde{w}^2 + \tilde{\gamma}_1^2 \right) d\Omega_2^* \right]^{\frac{1}{2}}, \quad C \neq 0.
\end{aligned}$$

Thus, one obtains

$$\begin{aligned}
& \langle S_2\varphi, \psi \rangle_{\Gamma_I} \leq \\
& \leq C_1^2 \left[ \int_{-1}^0 \left( \left( \frac{dw}{d\xi_1} \right)^2 + \left( \frac{dv_1}{d\xi_1} - \frac{h}{2} \frac{d\gamma_1}{d\xi_1} \right)^2 + w^2 + \left( v_1 - \frac{h}{2} \gamma_1 \right)^2 \right) d\Omega_2^* \right]^{\frac{1}{2}} \times \\
& \times \left[ \int_{-1}^0 \left( \left( \frac{d\tilde{w}}{d\xi_1} \right)^2 \left( \frac{d\tilde{v}_1}{d\xi_1} - \frac{h}{2} \frac{d\tilde{\gamma}_1}{d\xi_1} \right)^2 + \tilde{w}^2 + \left( \tilde{v}_1 - \frac{h}{2} \tilde{\gamma}_1 \right)^2 \right) d\Omega_2^* \right]^{\frac{1}{2}}, \quad C_1 \neq 0.
\end{aligned}$$

Let us consider now the local Steklov-Poincare operator  $S_1$ .



$$\begin{aligned} \langle S_1 \varphi, \psi \rangle_{\Gamma_I} &= \left\langle A_1 \left( 1 - k_1 \frac{h}{2} \right) G_I \sigma_{vv}(\varphi), \psi_1 \right\rangle_{\Gamma_I} + \\ &+ \left\langle A_1 \left( 1 - k_1 \frac{h}{2} \right) G_I \sigma_{v\tau}(\varphi), \psi_2 \right\rangle_{\Gamma_I}. \end{aligned}$$

It can be shown similarly to the case of linear elasticity that the operator  $S_1$  is coercive, symmetric, linear and continuous on  $H^{1/2}(\Gamma_I)$  [3, 6]. From the equivalence of the  $H^{1/2}(\Gamma_I)$  and  $L_2(\Gamma_I)$  norms with the use of Friedrichs' inequality, we obtain, that the operator  $S_1$  is linear, continuous, symmetric and coercive on  $H^1(\Gamma_I)$ .

To conclude, the Steklov-Poincare operator  $S$  is linear, continuous, symmetric and coercive on  $H^1(\Gamma_I)$  as the sum of the operators having such properties. By the Lax-Milgram lemma, our problem for the Steklov-Poincare operator has a unique solution on  $H^1(\Gamma_I)$ .

We remark that for the case of nonzero volume forces as well as nonzero boundary conditions, the proof can be carried out in a similar way.

Let  $Q$ ,  $Q_1$  and  $Q_2$  be the corresponding preconditioners in the domain decomposition algorithm [6]. It is known, that in the case of Dirichlet-Neumann iterations these preconditioners can be expressed through  $S_1$  and  $S_2$  as [6]

$$\begin{aligned} Q &= Q_1 + Q_2, \\ \langle Q_1 \varphi, \psi \rangle_{\Gamma_I} &= \langle S_1 \varphi, \psi \rangle_{\Gamma_I}, \\ \langle Q_2 \varphi, \psi \rangle_{\Gamma_I} &= \langle S_2 \varphi, \psi \rangle_{\Gamma_I} \end{aligned} \tag{10}$$

Since the Steklov-Poincare operators  $S_1$  and  $S_2$  are linear, continuous, symmetric and coercive on  $H^1(\Gamma_I)$ , we conclude that the operators  $Q$ ,  $Q_1$  and  $Q_2$  also possess these properties.

Therefore, by the convergence of the Dirichlet-Neumann iterations, the following method is convergent for  $0 < \theta < \theta_{max}$ :

$$\varphi^{k+1} = \varphi^k + \theta Q_2^{-1} (G - Q \varphi^k), \quad k = 0, 1, 2, \dots$$

where  $G$  is the right-hand side of the equation  $Q\varphi = G$ .

It is worth mentioning that all the properties of the continuous operators can be transferred to the corresponding discrete operators, and in the case of quasi-uniform mesh, these properties also hold for the discrete operators [6].

#### 4. NUMERICAL EXAMPLE

In this section we consider a rectangular object lying in  $\Omega$  that consists of a concrete main part in  $\Omega_1$  with a thin steel cover  $\Omega_2$  attached to its top. The physical dimensions are as follows:  $x_1^b = 0.05$ ,  $x_2^b = 0.05$ ,  $x_1^e = 1.05$ ,  $x_2^e = 0.55$ ,  $h = 0.02$ . The physical parameters for the main part are  $\nu = 0.33$ ,  $E = 25000MPa$ , for the shell -  $\nu = 0.33$ ,  $E = 200000MPa$ . The body is kept

fixed on both sides and subjected to the load on the bottom of  $p = 1\text{MPa}/\text{m}^2$  (see Fig. 2) with zero load on top.

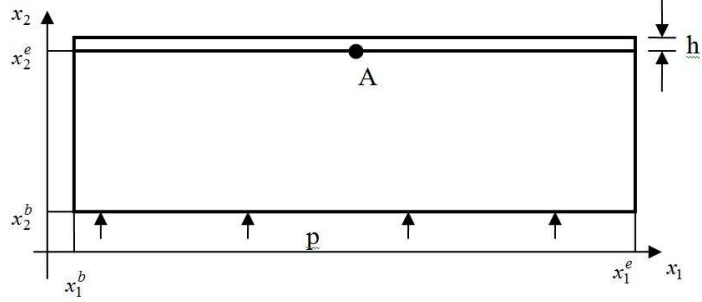


FIG. 2. Numerical Example

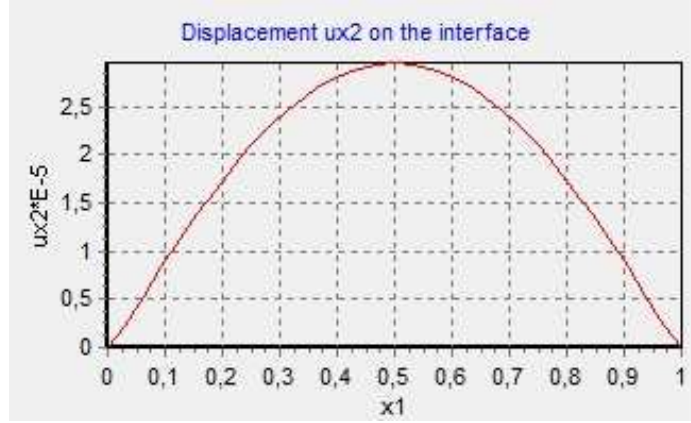


FIG. 3. Displacements in  $x_2$  direction on the interface

The solution on each iteration in the main part is done by BEM with linear basis functions with the Galerkin method applied to integral representation formula [1]

$$\frac{1}{2}u_i = \int_{\Gamma} (F_{ij}(x, y) t_j(y)) d\Gamma + \int_{\Gamma} (G_{ij}(x, y) u_j(y)) d\Gamma, \quad i = 1, 2,$$

where  $F_{ij}$  and  $G_{ij}$  are the Green's function and the co-normal derivative of Green's function respectively;  $t_i = \sigma_{ij}n_j$  are the tractions.

The solution in  $\Omega_2$  is sought as the linear combination of bubble basis functions which are defined on each element by

$$\Phi_0(\xi) = \frac{1-\xi}{2}, \quad \Phi_1(\xi) = \frac{1+\xi}{2}$$

$$\Phi_j(\xi) = \sqrt{\frac{2j-1}{2}} \int_{-1}^{\xi} P_{j-1}(t) dt, \quad j = 2, 3, \dots,$$

where  $P_j(\xi)$  are the Legendre polynomials. The solution in both domains is then combined using the iterative algorithm (10).

For our example we choose 96 equally spaced boundary elements. The relaxation parameter  $\theta$  is taken to be equal 0.00225

In Fig. 3 the displacement in  $x_2$  direction along the interface is shown. The displacement achieves its maximum in the middle point A of the interface.

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IVAN DYYAK, YAREMA SAVULA, ANDRIY STYAHAR,  
IVAN FRANKO NATIONAL UNIVERSITY OF LVIV,  
1, UNIVERSYTETS'KA STR., LVIV, 79000, UKRAINE

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