

Elastic Plates in Multibody Systems: A Treatment Using Existing Rigid Body Codes

PETER HAGEDORN and MARTIN BOTZ

Institut für Mechanik, TU Darmstadt, Hochschulstraße 1, 64289 Darmstadt, Germany

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Abstract. In the present paper, it is shown how one can employ existing rigid body codes to handle systems containing elastic plates by using a Rayleigh–Ritz discretization procedure. The equations of motion are formulated for a rectangular plate undergoing large rigid body motions, but small elastic deformations. Geometric nonlinearities in the elastic coordinates are taken into account to include the effect of dynamic stiffening. As an example, a spin-up maneuver for a simply-supported plate is treated.

Key words: elastic plates, elastic multibody systems, symbolic dynamics.

1. Introduction

The dynamic analysis of flexible multibody systems is a subject of current interest with applications in robotics and in the aerospace industry. Several authors have pointed out that one has to consider geometric nonlinearities in the elastic components to capture the effect of dynamic stiffening caused by the large rigid body motion of the structure [5, 10]. In [7, 9, 12], different theories for beams in large overall motion were presented; later, Banerjee and Kane [1] extended their analysis to plates.

In the present paper, a plate model similar to the one in [1] is chosen because the main objective is to show how one can employ an existing rigid body code to simulate motions of systems containing plates. As an example of an available code, originally developed for systems of rigid bodies only, the symbolic dynamics manipulator AUTODIV [8] is used. In [2] and [3], it was demonstrated that AUTODIV can be used to produce the equations of motion for multibody systems containing elastic beams. Now, it is shown that the theory is not limited to beam elements and that one can treat plates as well.

2. Analysis

We consider an arbitrary system containing rigid and elastic bodies. Discretizing the elastic parts via a Rayleigh–Ritz procedure may lead to a system possessing p degrees of freedom. The motion of the system in an inertial reference frame N , therefore, can be described by the generalized speeds u_1, \dots, u_p , which are

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Table of Contents Analysis Of Multibody Systems With Exible Plates Using

1. Understanding the eBook Analysis Of Multibody Systems With Exible Plates Using
 - The Rise of Digital Reading Analysis Of Multibody Systems With Exible Plates Using
 - Advantages of eBooks Over Traditional Books
2. Identifying Analysis Of Multibody Systems With Exible Plates Using
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Analysis Of Multibody Systems With Exible Plates Using
 - User-Friendly Interface
4. Exploring eBook Recommendations from Analysis Of Multibody Systems With Exible Plates Using
 - Personalized Recommendations
 - Analysis Of Multibody Systems With Exible Plates Using User Reviews and Ratings

- Analysis Of Multibody Systems With Exible Plates Using and Bestseller Lists
- 5. Accessing Analysis Of Multibody Systems With Exible Plates Using Free and Paid eBooks
 - Analysis Of Multibody Systems With Exible Plates Using Public Domain eBooks
 - Analysis Of Multibody Systems With Exible Plates Using eBook Subscription Services
 - Analysis Of Multibody Systems With Exible Plates Using Budget-Friendly Options
- 6. Navigating Analysis Of Multibody Systems With Exible Plates Using eBook Formats
 - ePub, PDF, MOBI, and More
 - Analysis Of Multibody Systems With Exible Plates Using Compatibility with Devices
 - Analysis Of Multibody Systems With Exible Plates Using Enhanced eBook Features
- 7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Analysis Of Multibody Systems With Exible Plates Using
 - Highlighting and Note-Taking Analysis Of Multibody Systems With Exible Plates Using
 - Interactive Elements Analysis Of Multibody Systems With Exible Plates Using
- 8. Staying Engaged with Analysis Of Multibody Systems With Exible Plates Using
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Analysis Of Multibody Systems With Exible Plates Using
- 9. Balancing eBooks and Physical Books Analysis Of Multibody Systems With Exible Plates Using
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Analysis Of Multibody Systems With Exible Plates Using
- 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
- 11. Cultivating a Reading Routine Analysis Of Multibody Systems With Exible Plates Using
 - Setting Reading Goals Analysis Of Multibody Systems With Exible Plates Using
 - Carving Out Dedicated Reading Time
- 12. Sourcing Reliable Information of Analysis Of Multibody Systems With Exible Plates Using
 - Fact-Checking eBook Content of Analysis Of Multibody Systems With Exible Plates Using
 - Distinguishing Credible Sources

13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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