

A 2D Time Domain DRBEM Computer Model for Magneto-Thermoelastic Coupled Wave Propagation Problems

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Abstract

A numerical computer model based on the dual reciprocity boundary element method (DRBEM) is extended to study magneto-thermoelastic coupled wave propagation problems with relaxation times involving anisotropic functionally graded solids. The model formulation is tested through its application to the problem of a solid placed in a constant primary magnetic field acting in the direction of the z-axis and rotating about this axis with a constant angular velocity. In the case of two-dimensional deformation, an implicit-explicit time domain DRBEM was presented and implemented to obtain the solution for the displacement and temperature fields. A comparison of the results is presented graphically in the context of Lord and Shulman (LS) and Green and Lindsay (GL) theories. Numerical results that demonstrate the validity of the proposed method are also presented graphically.

Keywords: magneto-thermo-elasticity, relaxation times, anisotropic, functionally graded solid, dual reciprocity boundary element method

1. Introduction

The dynamical interaction between the thermal and mechanical fields in anisotropic materials has great practical applications in modern aeronautics, astronautics, earthquake engineering, soil dynamics, mining engineering, nuclear reactors and high-energy particle accelerators, for instance. Lord and Shulman [1] developed the theory of generalized thermoelasticity with one relaxation time by constructing a new law of heat conduction to replace the classical Fourier's law. This law contains the heat flux vector as well as its time derivative. It contains also new constant that acts as relaxation time. Since the heat equation of this theory is the wave-type, it automatically ensures finite speeds of propagation for heat and elastic waves. Green and Lindsay [2] included a temperature rate among the constitutive variables to develop a temperature-rate-dependent thermoelasticity that does not violate the classical Fourier's law of heat conduction when the body under consideration has a center of symmetry; this theory also predicts a finite speed of heat propagation and is known as the theory of thermoelasticity with two relaxation times. According to these theories, heat propagation should be viewed as a wave phenomenon rather than diffusion one. Relevant theoretical developments on the subject were made by Green and Naghdi [3, 4], they developed three models for generalized thermoelasticity of homogeneous isotropic materials which are labeled as model I, II and III. These theories of thermoelasticity Lord and Shulman (LS), Green and Lindsay (GL) and Green and Naghdi (GN) theories are known as the generalized theories of thermoelasticity with finite thermal wave speed. It is hard to find the analytical solution of magneto-thermoelasticity problem in a general case, therefore, an important number of

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engineering and mathematical papers devoted to the numerical solution have studied the overall behavior of such materials (Das and Kanoria [5]; Huacasi et al. [6]; Paulino and Kim [7]; Abd-Alla et al. [8-10]; Fahmy [11-16]; Fahmy and El-Shahat [17]; Han and Hong [18]; Xiong and Tian [19]).

The first step of the boundary element method (BEM) is the transformation of the physical problem at hand to an integral equation. The latter is defined frequently solely on the boundary, in which case the dimensionality of the problem is reduced by one. The presence of domain integrals in the BEM formulation implies domain discretization and this makes the BEM inefficient when compared with domain discretization techniques such as finite element method (FEM) or finite difference method (FDM). Thus, many efforts have been made to convert the domain integral into a boundary one (Marin et al. [20]; Wen and Khonsari [21]; Javaran et al. [22]). One of the most widely used techniques to accomplish this task is the dual reciprocity boundary element method (DRBEM) developed by Nardini and Brebbia [23] in the context of two-dimensional (2D) elastodynamics and has been extended to deal with a variety of problems wherein the domain integral may account for linear-nonlinear static-dynamic effects (Brebbia et al. [24]; Wrobel and Brebbia [25]; Partridge and Brebbia [26]; Partridge and Wrobel [27]; Partridge et al. [28]; El-Naggar et al. [29, 30]; Gaul et al. [31]; Fahmy [32-34]).

The main purpose of this work is to study the generalized magneto-thermoelastic coupled wave propagation problems with relaxation times in anisotropic functionally graded solid placed in a constant primary magnetic field acting in the direction of the z-axis and rotating about this axis with a constant angular velocity. An implicit-explicit time integration procedure was developed and implemented for use with the dual reciprocity boundary element method (DRBEM) to obtain the solution for the governing equations of the considered problem. A comparison of the results is presented graphically in the context of LS and GL theories. Numerical results that demonstrate the validity of the proposed method are also presented graphically.

2. Formulation of the Problem

Consider a Cartesian coordinates system $Oxyz$ as shown in Fig. 1, we shall consider a functionally graded anisotropic solid placed in a primary magnetic field H_0 acting in the direction of the z-axis and rotating about it with a constant angular velocity. The solid occupies the region $R = \{(x, y, z): 0 < x < A, 0 < y < B, 0 < z < h\}$, the material properties are assumed to be graded through the x direction. Here we address the generalized two-dimensional deformation problem in xy -plane only. We also consider the following variant form of the power law material model $(x + 1)^m$, where m is a dimensionless constant.

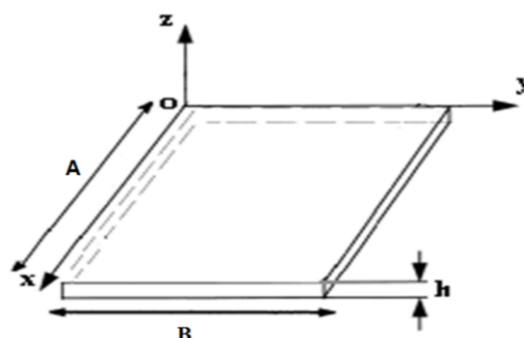


Fig. 1 The coordinate system of the solid

According to the Lord and Shulman ($\tau_1 = 0, \tau_0 > 0, \delta = 1$) and Green and Lindsay ($\tau_1 \geq \tau_0 > 0, \delta = 0$) theories, the governing equations for the generalized magneto-thermoelastic coupled wave propagation problems of anisotropic functionally graded solids in the absence of heat sources can be written in the following form:

$$\sigma_{ab,b} + \tau_{ab,b} - \rho(x+1)^m \omega^2 x_a = \rho(x+1)^m \ddot{u}_a \quad (1)$$

$$\sigma_{ab} = (x+1)^m [C_{abfg} u_{f,g} - \beta_{ab}(T - T_0 + \tau_1 \dot{T})] \quad (2)$$

$$\tau_{ab} = \mu(x+1)^m (\tilde{h}_a H_b + \tilde{h}_b H_a - \delta_{ba} (\tilde{h}_f H_f)) \quad (3)$$

$$k_{ab} T_{,ab} = \beta_{ab} T_0 [\dot{u}_{a,b} + \delta \tau_0 \ddot{u}_{a,b}] + \rho c (x+1)^m [\dot{T} + \tau_0 \ddot{T}] \quad (4)$$

3. Numerical Implementation

Making use of (2) and (3), we can write (1) as follows:

$$L_{gb} u_f = \rho \ddot{u}_a - (D_a T + D_{af} + \Lambda D_{a1f} - \rho \omega^2 x_a) = f_{gb} \quad (5)$$

where

$$L_{gb} = D_{abf} \frac{\partial}{\partial x_b}, D_{abf} = C_{abfg} \varepsilon, \varepsilon = \frac{\partial}{\partial x_g}, D_{af} = \mu H_0^2 \left(\frac{\partial}{\partial x_a} + \delta_{a1} \Lambda \right) \frac{\partial}{\partial x_f}, \Lambda = \frac{m}{x+1}, \quad (6)$$

$$D_a = -\beta_{ab} \left(\frac{\partial}{\partial x_b} + \delta_{b1} \Lambda + \tau_1 \left(\frac{\partial}{\partial x_b} + \Lambda \right) \frac{\partial}{\partial \tau} \right), f_{gb} = \rho \ddot{u}_a - (D_a T + D_{af} + \Lambda D_{a1f} - \rho \omega^2 x_a)$$

The field equations can now be written in operator form as follows,

$$L_{gb} u_f = f_{gb} \quad (7)$$

$$L_{ab} T = f_{ab} \quad (8)$$

where the operators L_{gb} and f_{gb} are defined in equation (5), and the operators L_{ab} and f_{ab} are defined as follows:

$$L_{ab} = k_{ab} \frac{\partial}{\partial x_a} \frac{\partial}{\partial x_b} \quad (9)$$

$$f_{ab} = \beta_{ab} T_0 [\dot{u}_{b,b} + \tau_0 \ddot{u}_{a,b}] + \rho c (x+1)^m [\dot{T} + \tau_0 \ddot{T}] \quad (10)$$

Using the weighted residual method (WRM), the differential equation (7) is transformed into an integral equation

$$\int_R (L_{gb} u_f - f_{gb}) u_{da}^* dR = 0 \quad (11)$$

Now, we choose the fundamental solution u_{df}^* as weighting function as follows,

$$L_{gb} u_{df}^* = -\delta_{ad} \delta(x, \xi) \quad (12)$$

The corresponding traction field can be written as

$$t_{da}^* = C_{abfg} u_{df,g}^* n_b \quad (13)$$

The thermoelastic traction vector can be written as follows,

$$t_a = (x+1)^m (C_{abfg} u_{f,g} - \beta_{ab}(T - T_0 + \tau_1 \dot{T})) n_b \quad (14)$$

Applying integration by parts to (11) using the sifting property of the Dirac distribution, with (12) and (14), we can write the following elastic integral representation formula

$$u_d(\xi) = \int_C (u_{da}^* t_a - t_{da}^* u_a + u_{da}^* \beta_{ab} T n_b) dC - \int_R f_{gb} u_{da}^* dR \quad (15)$$

The fundamental solution T^* of the thermal operator L_{ab} , defined by

$$L_{ab} T^* = -\delta(x, \xi) \quad (16)$$

By implementing the WRM and integration by parts, the differential equation (8) is transformed into the thermal reciprocity equation

$$\int_R (L_{ab} T T^* - L_{ab} T^* T) dR = \int_C (q^* T - q T^*) dC \quad (17)$$

where the heat fluxes are independent of the elastic field and can be expressed as follows:

$$q = -k_{ab} T_{,b} n_a \quad (18)$$

$$q^* = -k_{ab} T_{,b}^* n_a \quad (19)$$

By the use of sifting property, we obtain from (17) the thermal integral representation formula

$$T(\xi) = \int_C (q^* T - q T^*) dC - \int_R f_{ab} T^* dR \quad (20)$$

The integral representation formulae of elastic and thermal fields (15) and (20) can be combined to form a single equation as follows,

$$\begin{bmatrix} u_d(\xi) \\ T(\xi) \end{bmatrix} = \int_C \left\{ - \begin{bmatrix} t_{da}^* & -u_{da}^* \beta_{ab} n_b \\ 0 & -q^* \end{bmatrix} \begin{bmatrix} u_a \\ T \end{bmatrix} + \begin{bmatrix} u_{da}^* & 0 \\ 0 & -T^* \end{bmatrix} \begin{bmatrix} t_a \\ q \end{bmatrix} \right\} dC - \int_R \begin{bmatrix} u_{da}^* & 0 \\ 0 & -T^* \end{bmatrix} \begin{bmatrix} f_{gb} \\ -f_{ab} \end{bmatrix} dR \quad (21)$$

It is convenient to use the contracted notation to introduce generalized thermoelastic vectors and tensors, which contain corresponding elastic and thermal variables as follows:

$$U_{\bar{A}} = \begin{cases} u_a & a = \bar{A} = 1, 2, 3 \\ T & \bar{A} = 4 \end{cases} \quad (22)$$

$$T_{\bar{A}} = \begin{cases} t_a & a = \bar{A} = 1, 2, 3 \\ q & \bar{A} = 4 \end{cases} \quad (23)$$

$$U_{d\bar{A}}^* = \begin{cases} u_{da}^* & d = D = 1, 2, 3; a = \bar{A} = 1, 2, 3 \\ 0 & d = D = 1, 2, 3; \bar{A} = 4 \\ 0 & D = 4; a = \bar{A} = 1, 2, 3 \\ -T^* & D = 4; \bar{A} = 4 \end{cases} \quad (24)$$

$$\tilde{T}_{D\bar{A}}^* = \begin{cases} t_{da}^* & d = D = 1, 2, 3; a = \bar{A} = 1, 2, 3 \\ -\tilde{u}_d^* & d = D = 1, 2, 3; \bar{A} = 4 \\ 0 & D = 4; a = \bar{A} = 1, 2, 3 \\ -q^* & D = 4; \bar{A} = 4 \end{cases} \quad (25)$$

$$\tilde{u}_d^* = u_{da}^* \beta_{af} n_f \quad (26)$$

The thermoelastic representation formula (21) can be written in contracted notation as:

$$U_D(\xi) = \int_C (U_{D\bar{A}}^* T_{\bar{A}} - \tilde{T}_{D\bar{A}} U_{\bar{A}}) dC - \int_R U_{B\bar{A}}^* S_{\bar{A}} dR \quad (27)$$

The vector $S_{\bar{A}}$ can be written in the split form as follows:

$$S_{\bar{A}} = S_{\bar{A}}^0 + S_{\bar{A}}^T + S_{\bar{A}}^u + S_{\bar{A}}^{\dot{T}} + S_{\bar{A}}^{\dot{T}} + S_{\bar{A}}^{\dot{u}} + S_{\bar{A}}^{\dot{u}} \quad (28)$$

where

$$S_{\bar{A}}^0 = \begin{cases} \rho\omega^2 x_a & a = \bar{A} = 1, 2, 3 \\ 0 & \bar{A} = 4 \end{cases} \quad (29)$$

$$S_{\bar{A}}^T = \omega_{\bar{A}F} U_F \quad \text{with} \quad \omega_{\bar{A}F} = \begin{cases} -D_{a\bar{A}} & a = \bar{A} = 1, 2, 3; F = 4 \\ 0 & \text{otherwise} \end{cases} \quad (30)$$

$$S_{\bar{A}}^u = -(D_{af} + \Lambda D_{a1f}) \mathcal{U} U_F \quad \text{with} \quad \mathcal{U} = \begin{cases} 1 & a = \bar{A} = 1, 2, 3; f = F = 1, 2, 3 \\ 0 & \text{otherwise} \end{cases} \quad (31)$$

$$S_{\bar{A}}^{\dot{T}} = -\rho c(x+1)^m \delta_{\bar{A}F} \dot{U}_F \quad \text{with} \quad \delta_{\bar{A}F} = \begin{cases} 1 & \bar{A} = 4; F = 4 \\ 0 & \text{otherwise} \end{cases} \quad (32)$$

$$S_{\bar{A}}^{\dot{T}} = -\rho c(x+1)^m \tau_0 \delta_{\bar{A}F} \ddot{U}_F \quad (33)$$

$$S_{\bar{A}}^{\dot{u}} = -T_0 \beta_{ab} \varepsilon \dot{U}_F \quad (34)$$

$$S_{\bar{A}}^{\dot{u}} = \mathfrak{d} \ddot{U}_F \quad \text{with} \quad \mathfrak{d} = \begin{cases} \rho & \bar{A} = 1, 2, 3; F = 1, 2, 3 \\ -T_0 \beta_{ab} \tau_0 \varepsilon & \bar{A} = 4; f = F = 4 \end{cases} \quad (35)$$

The thermoelastic representation formula (21) can also be written in matrix form as follows:

$$[S_{\bar{A}}] = \begin{bmatrix} \rho\omega^2 x_a \\ 0 \end{bmatrix} + \begin{bmatrix} -D_a T \\ 0 \end{bmatrix} + \begin{bmatrix} -(D_{af} + \Lambda D_{a1f}) u_f \\ 0 \end{bmatrix} + \begin{bmatrix} 0 \\ -\rho c(x+1)^m \dot{T} \end{bmatrix} + \begin{bmatrix} 0 \\ -\rho c(x+1)^m \tau_0 \ddot{T} \end{bmatrix} + \begin{bmatrix} 0 \\ -T_0 \beta_{ab} \dot{u}_{a,b} \end{bmatrix} + \begin{bmatrix} \rho \dot{u}_a \\ -T_0 \beta_{ab} \tau_0 \ddot{u}_{a,b} \end{bmatrix} \quad (36)$$

Our task now is to implement the DRBEM. To transform the domain integral in (27) to the boundary, we approximate the source vector $S_{\bar{A}}$ in the domain as usual by a series of given tensor functions $f_{\bar{A}N}^q$ and unknown coefficients α_N^q

$$S_{\bar{A}} \approx \sum_{q=1}^E f_{\bar{A}N}^q \alpha_N^q \quad (37)$$

According to the DRBEM, the surface of the solid has to be discretized into boundary elements. In order to make the implementation easy to compute, we use N_b collocation points on the boundary C and another N_i in the interior of R so that the total number of interpolation points is $N = N_b + N_i$.

Thus, the thermoelastic representation formula (27) can be written in the following form,

$$U_D(\xi) = \int_C (U_{D\bar{A}}^* T_{\bar{A}} - \tilde{T}_{D\bar{A}}^* U_{\bar{A}}) dC - \sum_{q=1}^N \int_R U_{D\bar{A}}^* f_{\bar{A}N}^q dR \alpha_N^q \quad (38)$$

By applying the WRM to the following inhomogeneous elastic and thermal equations:

$$L_{gb}u_{fn}^q = f_{an}^q \tag{39}$$

$$L_{ab}T^q = f_{pj}^q \tag{40}$$

The elastic and thermal representation formulae are as follows (Fahmy [35]),

$$u_{de}^q(\xi) = \int_C (u_{da}^* t_{ae}^q - t_{da}^* u_{ae}^q) dC - \int_R u_{da}^* f_{ae}^q dR \tag{41}$$

$$T^q(\xi) = \int_C (q^* T^q - q^q T^*) dC - \int_R f^q T^* dR \tag{42}$$

The dual representation formulae of elastic and thermal fields can be combined to form a single equation as follows,

$$U_{DN}^q(\xi) = \int_C (U_{D\bar{A}}^* T_{\bar{A}N}^q - T_{D\bar{A}}^* U_{\bar{A}N}^q) dC - \int_R U_{D\bar{A}}^* f_{\bar{A}N}^q dR \tag{43}$$

With the substitution of (43) into (38), the dual reciprocity representation formula of coupled thermoelasticity can be expressed as follows,

$$U_D(\xi) = \int_C (U_{D\bar{A}}^* T_{\bar{A}} - \check{T}_{D\bar{A}}^* U_{\bar{A}}) dC + \sum_{q=1}^N \left(U_{DN}^q(\xi) + \int_C (T_{D\bar{A}}^* U_{\bar{A}N}^q - U_{D\bar{A}}^* T_{\bar{A}N}^q) dC \right) \alpha_N^q \tag{44}$$

To calculate interior stresses, (44) is differentiated with respect to ξ_l as follows,

$$\begin{aligned} \frac{\partial U_D(\xi)}{\partial \xi_l} = & - \int_C (U_{D\bar{A},l}^* T_{\bar{A}} - \check{T}_{D\bar{A},l}^* U_{\bar{A}}) dC \\ & + \sum_{q=1}^N \left(\frac{\partial U_{DN}^q(\xi)}{\partial \xi_l} - \int_C (T_{D\bar{A},l}^* U_{\bar{A}N}^q - U_{D\bar{A},l}^* T_{\bar{A}N}^q) dC \right) \alpha_N^q \end{aligned} \tag{45}$$

According to the steps described in Fahmy [36], the dual reciprocity boundary integral equation (44) can be written in the following system of equations:

$$\check{\zeta}\check{u} - \eta\check{t} = (\zeta\check{U} - \eta\check{\rho})\alpha \tag{46}$$

The technique was proposed by Partridge et al. [27] can be extended to treat the convective terms, then the generalized displacements U_F and velocities \dot{U}_F are approximated by a series of tensor functions f_{FD}^q and unknown coefficients γ_D^q and $\check{\gamma}_D^q$

$$U_F \approx \sum_{q=1}^N f_{FD}^q(x) \gamma_D^q \tag{47}$$

$$\dot{U}_F \approx \sum_{q=1}^N f_{FD}^q(x) \check{\gamma}_D^q \tag{48}$$

The gradients of the generalized displacement and velocity can be approximated as follows,

$$U_{F,g} \approx \sum_{q=1}^N f_{FD,g}^q(x) \gamma_K^q \quad (49)$$

$$\dot{U}_{F,g} \approx \sum_{q=1}^N f_{FD,g}^q(x) \tilde{\gamma}_D^q \quad (50)$$

These approximations are substituted into equations (30) and (34) to approximate the corresponding source terms as follows,

$$S_{\bar{A}}^T = \sum_{q=1}^N S_{\bar{A}D}^{T,q} \gamma_D^q \quad (51)$$

$$S_{\bar{A}}^{\dot{u}} = -T_0 \beta_{ab} \varepsilon \sum_{q=1}^N S_{\bar{A}D}^{\dot{u},q} \tilde{\gamma}_D^q \quad (52)$$

where

$$S_{\bar{A}B}^{T,q} = S_{\bar{A}F} f_{FD,g}^q \quad (53)$$

$$S_{\bar{A}D}^{\dot{u},q} = S_{F\bar{A}} f_{FD,g}^q \quad (54)$$

The same point collocation procedure described in Gaul, et al. [31] can be applied to (37), (47) and (48). This leads to the following system of equations,

$$\check{S} = J\alpha, \quad U = J'\gamma, \quad \dot{U} = J'\tilde{\gamma} \quad (55)$$

Similarly, the application of the point collocation procedure to the source terms equations (31), (32), (33), (35), (51) and (52) leads to the following system of equations:

$$\check{S}^u = -(D_{af} + \Lambda D_{a1f}) \mathbb{U} U_F \text{ with } \mathbb{U} = \begin{cases} 1 & a = \bar{A} = 1, 2, 3; f = F = 1, 2, 3 \\ 0 & \text{otherwise} \end{cases} \quad (56)$$

$$\check{S}^T = -\rho c (x+1)^m \delta_{\bar{A}F} \dot{U} \quad (57)$$

$$\check{S}^{\ddot{r}} = -c\rho (x+1)^m \tau_0 \delta_{\bar{A}F} \ddot{U} \quad (58)$$

$$\check{S}^{\dot{u}} = \tilde{A} \dot{U} \quad (59)$$

$$\check{S}^T = \mathcal{B}^T \gamma \quad (60)$$

$$\check{S}^{\dot{u}} = -T_0 \beta_{ab} \varepsilon \mathcal{B}^{\dot{u}} \tilde{\gamma} \quad (61)$$

Solving the system (55) for α , γ and $\tilde{\gamma}$ yields

$$\alpha = J^{-1} \check{S} \quad \gamma = J'^{-1} U \quad \tilde{\gamma} = J'^{-1} \dot{U} \quad (62)$$

Now, the coefficients α can be expressed in terms of nodal values of the unknown displacements U , velocities \check{U} and accelerations $\check{\check{U}}$ as follows:

$$\alpha = J^{-1}(\check{S}^0 + [B^T J'^{-1} - (D_{af} + \Lambda D_{a1f})\check{U}]U - [\rho c(x+1)^m \delta_{AF} + T_0 \beta_{ab} \varepsilon B^u J'^{-1}]\check{U} + [\check{A} - c\rho(x+1)^m \tau_0 \delta_{AF}]\check{\check{U}}) \quad (63)$$

where \check{A} and B^T are assembled using the submatrices $[d]$ and $[\omega_{AF}]$ respectively.

Substituting from Eq. (63) into Eq. (46), we obtain (Fahmy [37])

$$M\check{\check{U}} + \Gamma\check{U} + KU = \mathbb{Q} \quad (64)$$

in which M, Γ, K and \mathbb{Q} are independent of time and are defined by

$$V = (\eta\check{\check{\phi}} - \zeta\check{U})J^{-1}, \quad \check{M} = V[\check{A} - c\rho(x+1)^m \tau_0 \delta_{AF}],$$

$$\Gamma = V[-\rho c(x+1)^m \delta_{AF} - T_0 \beta_{fg} \varepsilon B^u J'^{-1}], \quad (65)$$

$$K = \check{\zeta} + V[B^T J'^{-1} + (D_{af} + \Lambda D_{a1f})\check{U}], \quad \mathbb{Q} = \eta T + V\check{S}^0.$$

where V, M, Γ and K represent the volume, mass, damping and stiffness matrices, respectively; $\check{\check{U}}, \check{U}, U$ and \mathbb{Q} represent the acceleration, velocity, displacement and external force vectors, respectively. The initial value problem consists of finding the function $U = U(\tau)$ satisfying equation (64) and the initial conditions $U(0) = U_0, \check{U}(0) = V_0$ where U_0, V_0 are given vectors of initial data. Then, from Eq. (78), we can compute the initial acceleration vector W_0 as follows (Prevost and Tao [38])

$$MW_0 = \mathbb{Q}_0 - \Gamma V_0 - K U_0 \quad (66)$$

An implicit-explicit time integration algorithm of Hughes and Liu [39, 40] was presented and implemented for use with the DRBEM. This algorithm consists of satisfying the following equations

$$M\check{\check{U}}_{n+1} + \Gamma^I \check{U}_{n+1} + \Gamma^E \check{\check{U}}_{n+1} + K^I U_{n+1} + K^E \check{U}_{n+1} = \mathbb{Q}_{n+1} \quad (67)$$

$$U_{n+1} = \check{U}_{n+1} + \gamma \Delta\tau^2 \check{\check{U}}_{n+1} \quad (68)$$

$$\check{U}_{n+1} = \check{\check{U}}_{n+1} + \alpha \Delta\tau \check{\check{U}}_{n+1} \quad (69)$$

where

$$\check{\check{U}}_{n+1} = U_{n+1} + \Delta\tau \check{U}_n + (1 - 2\gamma) \frac{\Delta\tau^2}{2} \check{\check{U}}_n \quad (70)$$

$$\check{\check{U}}_{n+1} = \check{U}_n + (1 - \alpha) \Delta\tau \check{\check{U}}_n \quad (71)$$

in which the implicit and explicit parts are respectively denoted by the superscripts I and E . Also, we used the quantities $\check{\check{U}}_{n+1}$ and \check{U}_{n+1} to denote the predictor values, and U_{n+1} and \check{U}_{n+1} to denote the corrector values. It is easy to recognize that the equations (68)-(71) correspond to the Newmark formulas (Newmark [41]).

At each time-step, equations (67)-(71), constitute an algebraic problem in terms of the unknown $\check{\check{U}}_{n+1}$. The first step in the code starts by forming and factoring the effective mass

$$M^* = M + \gamma \Delta\tau C^I + \gamma \Delta\tau^2 K^I \quad (72)$$

The time step $\Delta\tau$ must be constant to run this step. As the time-step $\Delta\tau$ is changed, the first step should be repeated at each new step. The second step is to form residual force

$$\mathbb{Q}_{n+1}^* = \mathbb{Q}_{n+1} - C^I \tilde{U}_{n+1} - C^E \tilde{U}_{n+1} - K^I \tilde{U}_{n+1} - K^E \tilde{U}_{n+1} \quad (73)$$

Note that in the implicit part, M^* is always non-symmetric. However, M^* still possesses the usual "band-profile" structure associated with the connectivity of the DRBEM mesh, and has a symmetric profile. So the third step is to solve $M^* \ddot{U}_{n+1} = \mathbb{Q}_{n+1}^*$ using a Crout elimination algorithm (Taylor [42]) which fully exploits that structure in that zeroes outside the profile are neither stored nor operated upon. The fourth step is to use predictor-corrector equations (68) and (69) to obtain the corrector displacement and velocity vectors, respectively.

4. Numerical Results and Discussion

Following Rasolofosaon and Zinszner [43] monoclinic North Sea sandstone reservoir rock was chosen as an anisotropic material and physical data are as follows:

Elasticity tensor

$$C_{ijkl} = \begin{bmatrix} 17.77 & 3.78 & 3.76 & 0.24 & -0.28 & 0.03 \\ 3.78 & 19.45 & 4.13 & 0 & 0 & 1.13 \\ 3.76 & 4.13 & 21.79 & 0 & 0 & 0.38 \\ 0 & 0 & 0 & 8.30 & 0.66 & 0 \\ 0 & 0 & 0 & 0.66 & 7.62 & 0 \\ 0.03 & 1.13 & 0.38 & 0 & 0 & 7.77 \end{bmatrix} \text{GPa} \quad (74)$$

Mechanical temperature coefficient

$$\beta_{pj} = \begin{bmatrix} 0.001 & 0.02 & 0 \\ 0.02 & 0.006 & 0 \\ 0 & 0 & 0.05 \end{bmatrix} \cdot 10^6 \text{ N/Km}^2 \quad (75)$$

Tensor of thermal conductivity is

$$k_{pj} = \begin{bmatrix} 1 & 0.1 & 0.2 \\ 0.1 & 1.1 & 0.15 \\ 0.2 & 0.15 & 0.9 \end{bmatrix} \text{W/(mK)} \quad (76)$$

Mass density $\rho = 2216 \text{ kg/m}^3$ and heat capacity $c = 0.1 \text{ J/(kg K)}$, $H_0 = 1000000 \text{ Oersted}$, $\mu = 0.5 \text{ Gauss/Oersted}$, $\kappa = 2$, $h = 2$, $\Delta\tau = 0.0001$. The numerical values of the temperature and displacement are obtained by discretizing the boundary into 120 elements ($N_b = 120$) and choosing 60 well spaced out collocation points ($N_i = 60$) in the interior of the solution domain, refer to the recent work of Fahmy [44-46].

The initial and boundary conditions considered in the calculations are

$$\text{at } \tau = 0 \quad \dot{u}_1 = \dot{u}_2 = \ddot{u}_1 = \ddot{u}_2 = 0, \quad T = 0 \quad (77)$$

$$\text{at } x = 0 \quad \frac{\partial u_1}{\partial x} = \frac{\partial u_2}{\partial x} = 0, \quad \frac{\partial T}{\partial x} = 0 \quad (78)$$

$$\text{at } x = A \quad \frac{\partial u_1}{\partial x} = \frac{\partial u_2}{\partial x} = 0, \quad \frac{\partial T}{\partial x} = 0 \quad (79)$$

$$\text{at } y = 0 \quad \frac{\partial u_1}{\partial y} = \frac{\partial u_2}{\partial y} = 0, \quad \frac{\partial T}{\partial y} = 0 \quad (80)$$

$$\text{at } y = B \quad \frac{\partial u_1}{\partial y} = \frac{\partial u_2}{\partial y} = 0, \quad \frac{\partial T}{\partial y} = 0 \quad (81)$$

Figures 2 and 3 show the variation of the temperature T with time τ . We can conclude from these figures that the maximum temperature T occurs at $\tau = 3$ in the LS theory, but it occurs at $\tau = 6$ in the GL theory. It is seen also from these figures that the oscillation period in the GL is less than the oscillation period in LS theory.

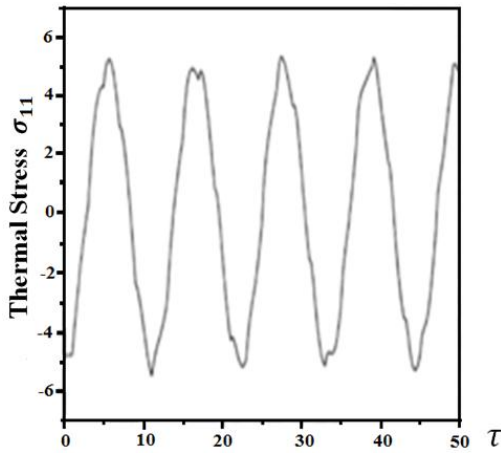


Fig. 2 Variation of thermal stress σ_{11} with time τ (LS)

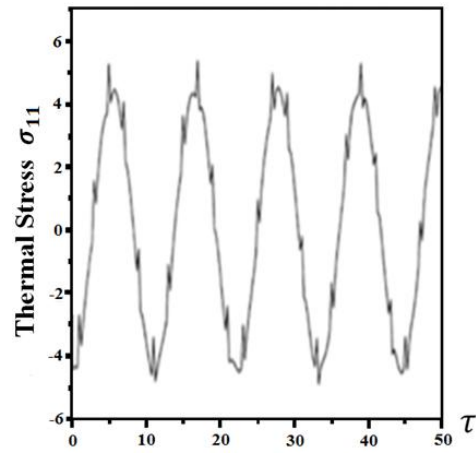


Fig. 3 Variation of the thermal stress σ_{11} with time τ (GL)

Figures 4 and 5 show the variation of the displacement u_1 with time τ . It may be seen from these figures that the displacement u_1 appears to have an intense oscillation. The oscillation period of LS theory is less than the oscillation period of GL theory. It can be seen that the maximum displacement u_1 occurs at $\tau = 11$ for the LS theory, but it occurs at $\tau = 33$ for the GL theory. The minimum magnitude of displacement u_1 occurs at homogeneous case.

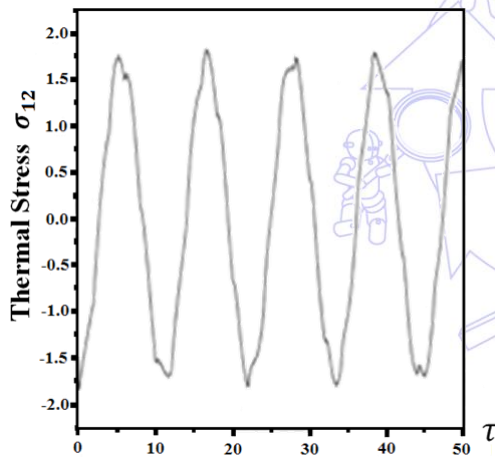


Fig. 4 Variation of the thermal stress σ_{12} with time τ (LS)

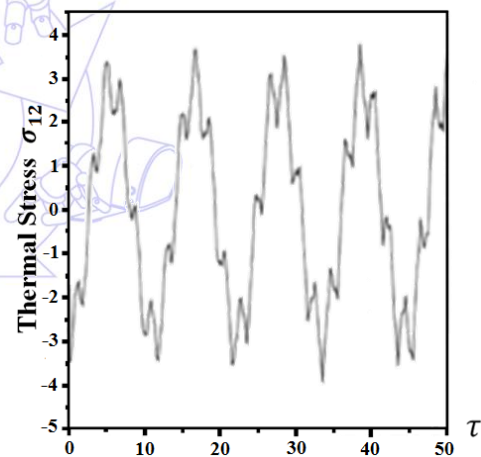


Fig. 5 Variation of the thermal stress σ_{12} with time τ (GL)

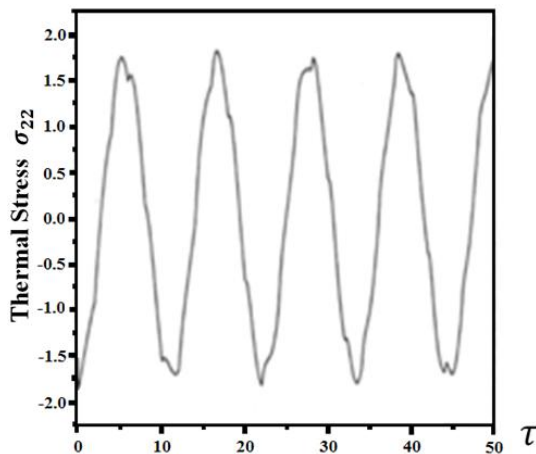


Fig. 6 Variation of the thermal stress σ_{22} with time τ (LS)

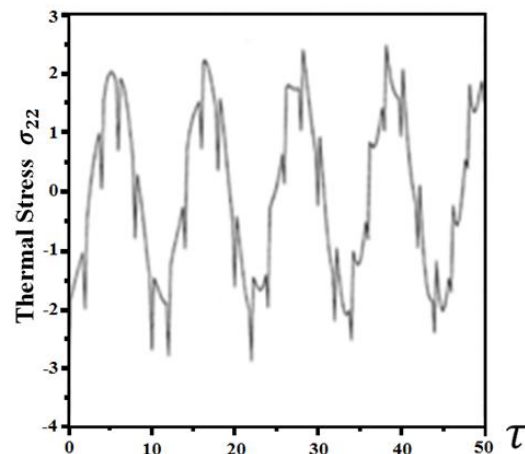


Fig. 7 Variation of the thermal stress σ_{22} with time τ (GL)

Figures 6 and 7 illustrate the variation of the displacement u_2 with time τ . It may be seen from these figures that the displacement u_2 appears to have an intense oscillation. The oscillation period of LS theory is less than the oscillation period of GL theory. It can be seen from these figures that the maximum displacement u_2 occurs at $\tau = 22.5$ for the LS theory. But it occurs at $\tau = 33.5$ for the GL theory.

Figures 2-7 show the difference between the LS and GL theories for the thermal stresses σ_{11} , σ_{12} and σ_{22} at $(0.5, 0.5)$. We can see also from these figures that the thermal stresses appear in an intense oscillation.

Figures 2 and 3 illustrate the variation of the thermal stress σ_{11} with time τ . It can be seen that the maximum thermal stress σ_{11} occurs at $\tau = 27.5$ for the LS theory. But it occurs at $\tau = 17$ for the GL theory.

Figures 4 and 5 show the variation of the thermal stress σ_{12} with time τ . It can be seen that the maximum thermal stress σ_{12} occurs at $\tau = 17$ for the LS theory. But it occurs at $\tau = 38$ for the GL theory.

Figures 6 and 7 illustrate the variation of the thermal stress σ_{22} with time τ . It can be seen that the maximum thermal stress σ_{22} occurs at $\tau = 38$ for the GL theory. But it occurs at $\tau = 17$ for the LS theory.

It can be noted from these figures that the maximum thermal stress occurs in GL theory. It is seen also from these figures that the oscillation period of LS theory is less than the oscillation period of GL theory for the thermal stresses σ_{12} and σ_{22} . But the oscillation period of GL theory is less than the oscillation period of LS theory for the thermal stress σ_{11} .

The present work should be applicable to any dynamic coupled magneto-thermoelastic deformation problem. The proposed technique in the present study was discussed in the context of the viscoelastic problems in Fahmy [47, 48] and discussed in the context of the generalized theories of thermoelasticity in Fahmy et al. [49-52]. The example considered by Mojdehi et al. [53], may be also considered as a special case of the current general study. Also, there are a lot of practical applications may be deduced as special cases from this general study and may be implemented in commercial finite element method (FEM) software packages FlexPDE 6.

In the special case under consideration, the results are plotted in figures 8-10 to show the validity of the DRBEM. These results obtained with the DRBEM have been compared graphically with those obtained using the Meshless Local Petrov-Galerkin (MLPG) method of Mojdehi et al. [53] and also the results obtained from the FlexPDE 6 are shown graphically in the same figures to confirm the validity of the proposed method. It can be seen from these figures that the DRBEM results are in excellent agreement with the results obtained by MLPG and FEM, thus confirming the accuracy of the DRBEM.

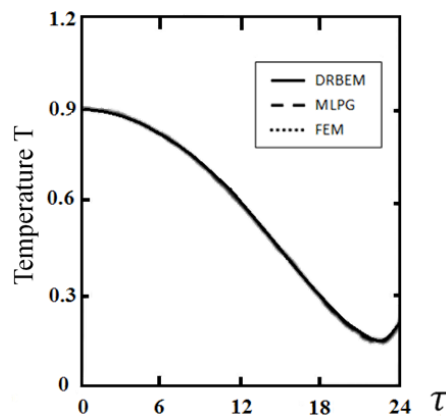


Fig. 8 Variation of the temperature T with time τ for three methods: DRBEM, MLPG and FEM

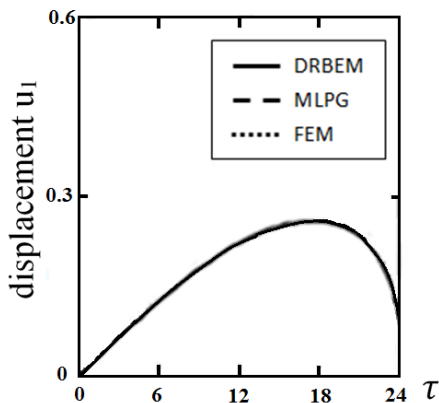


Fig. 9 Variation of the displacement u_1 with time τ for three methods: DRBEM, MLPG and FEM

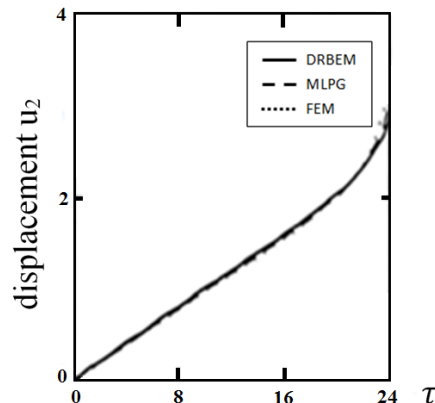


Fig. 10 Variation of the displacement u_2 with time τ for three methods: DRBEM, MLPG and FEM

Nomenclature			
u_k	components of displacement	τ	time
T	temperature	\tilde{h}	perturbed magnetic field
c	specific heat capacity	H	magnetic intensity vector
μ	magnetic permeability	ρ	density
σ_{ab}	mechanical stress tensor	C_{abfg}	constant elastic moduli
τ_{ab}	Maxwell's electromagnetic stress tensor	β_{ab}	stress-temperature coefficients
k_{ab}	heat conductivity coefficients	ω	uniform angular velocity
t_a	$= \sigma_{ab}n_b$, tractions	T_0	reference temperature
τ_0, τ_1	relaxation times		

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