

ANALYSIS OF CONTINUOUS RECTANGULAR PLATES ON FLEXIBLE  
BEAM SUPPORTS BY FLEXIBILITY METHODS

By

VATTI ARLA REDDY

Bachelor of Engineering

Sri Venkateswara University

Tirupathi, India

1958

Submitted to the Faculty of the Graduate School of  
the Oklahoma State University  
in partial fulfillment of the requirements  
for the degree of  
MASTER OF SCIENCE  
May, 1963

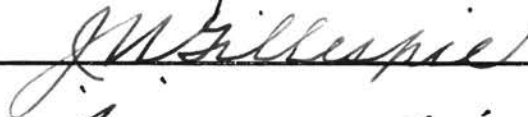
JAN 8 1964

ANALYSIS OF CONTINUOUS RECTANGULAR PLATES ON FLEXIBLE  
BEAM SUPPORTS BY FLEXIBILITY METHODS

Thesis Approved:



Thesis Adviser





Dean of the Graduate School

542155

## ACKNOWLEDGEMENTS

The writer wishes to express his sincere appreciation and gratitude to the following individuals:

To Dr. Kerry S. Havner, his major adviser, for his able guidance, constructive criticism and encouragement throughout the preparation of this study;

To Professor Jan J. Tuma for his assistance and interest in my studies;

To the Faculty of the School of Civil Engineering for their valuable instruction;

To his parents Shouri Reddy and Thecklamma for their complete understanding and financial support for his graduate work;

To Mr. Marr for his cooperation during the preparation of the manuscript;

And to Mrs. Marilyn Bond for her painstaking effort in typing this study.

V. Arla Reddy

## TABLE OF CONTENTS

Chapter	Page
I. INTRODUCTION . . . . .	1
1.1 Preliminary Remarks . . . . .	1
1.2 Scope of Study . . . . .	2
II. DEFLECTION INFLUENCE COEFFICIENTS BY FINITE DIFFERENCES . . .	3
2.1 General Finite Difference Equation . . . . .	3
2.2 Finite Difference Equations for Typical Points Near the Edges . . . . .	7
2.3 Deflection Influence Coefficients . . . . .	14
III. GENERAL MOMENT AND REACTION EQUATIONS . . . . .	17
3.1 Derivation of Moment and Reaction Equations . . . . .	17
IV. ANGULAR AND DISPLACEMENT FUNCTIONS . . . . .	27
4.1 Angular and Displacement Load Functions . . . . .	27
4.2 Angular and Angular-Displacement Flexibilities . . . . .	28
4.3 Angular and Angular-Displacement Carry-Overs . . . . .	30
4.4 Displacement Flexibility and Carry-Over . . . . .	31
4.5 Beam Flexibilities . . . . .	32
V. NUMERICAL EXAMPLE . . . . .	37
VI. SUMMARY AND CONCLUSIONS . . . . .	49
6.1 Summary . . . . .	49
6.2 Findings and Conclusions . . . . .	49
BIBLIOGRAPHY . . . . .	50

LIST OF TABLES

Table	Page
5.1 Deflection Influence Coefficients for Basic Panel . . . . .	39
5.2 Deflection Influence Coefficients for Beam . . . . .	45

## LIST OF FIGURES

Figure	Page
2.1 Basic Plate Structure . . . . .	3
2.2 Grid Network . . . . .	4
2.3 Typical Points Near the Edges . . . . .	8
2.4 Resolution of Antisymmetrical Loaded Symmetrical Plate . . . . .	16
3.1 General Structure . . . . .	17
3.2 Slope Compatibility of Adjacent Panels . . . . .	18
3.3 Displacement Compatibility . . . . .	19
3.4 Reactions Between Plates and Supporting Beam . . . . .	21
3.5 Continuous Supporting Beam . . . . .	23
4.1 Angular Load and Displacement Functions . . . . .	27
4.2 Angular and Angular-Displacement Flexibilities . . . . .	29
4.3 Angular and Angular-Displacement Carry-Overs . . . . .	30
4.4 Displacement Flexibility and Carry-Over . . . . .	32
4.5 Angular and Displacement Load Functions of Beam . . . . .	33
4.6 Displacement Flexibility and Carry-Overs of Beam . . . . .	34
4.7 Angular Flexibilities and Carry-Over Functions of Beam . . . . .	35
5.1 Continuous Plate Structure . . . . .	37
5.2 Basic Panel . . . . .	38
5.3 Reduced Plate Structure Due to Symmetry . . . . .	46

## NOMENCLATURE

a, b	Carry-Over Factors
c, c', d, d'	Dimensionless Quantities
i, j, k	Network Points
p	Intensity of Load
t	Dimensionless Quantity
x, y	Rectangular Co-ordinates, Co-ordinate Axes
D	Flexural Rigidity of Plate
$D_{ii}$	Displacement Flexibility
E	Young's Modulus of Elasticity
$F_{ii}$	Angular Flexibility
$G_{ij}$	Angular Carry-Over
$H_{ij}$	Displacement Carry-Over
I	Flexural Rigidity of Beam
M	Sum of Bending Moments $\times \frac{1}{(1+\nu)}$
O	Origin of Co-ordinate System
P	Concentrated Load
$Q_{ij}$	Angular-Displacement Carry-Over
R	Vertical Edge Reaction Per Unit Length
w	Vertical Deflection
$\delta$	Displacement Load Function
$\eta$	Deflection Influence Coefficient
$\theta$	Angle of Rotation of Plate

$\lambda$	Dimensionless Quantity
$\nu$	Poisson's Ratio
$\tau$	Angular Load Function
$\Delta A$	Area of the Domain of Point $ij$
$\Delta x, \Delta y$	Dimensions of Plate Element



## CHAPTER I

### INTRODUCTION

1.1. Preliminary Remarks. Continuous rectangular plates can broadly be classified into two groups depending upon the number of directions of continuity. "One-way" continuous plates are those that are continuous over supports in only one direction, and "two-way" continuous plates are those that are continuous in two mutually orthogonal directions.

One-way rectangular plates continuous over rigid supports have been treated by Marcus (1), Jensen (2) and Hawk (3). Newmark (4) extended the distribution method to one-way continuous plates over flexible supports.

Rigorous solutions for two-way continuous plates are available for limited special cases only. Southerland, et. al. (5) and Neilson (6) treated the problem of a plate consisting of a number of identical panels and supported by beams of equal stiffness. Approximate solutions of two-way continuous plates over rigid supports have been presented by Bittner (7) and Maugh and Pan (8). Engelbreth (9) and Newmark (10) independently developed approximate distribution procedures for determining the total moments across any section for plates continuous over rigid beams.

Lechter (11) extended the flexibility method to two-way continuous plates over rigid supports. The basic structure in this approach was a simply supported rectangular plate. Angular functions were defined in terms of influence coefficients for deflection of a simple plate obtained from a set of tables prepared by Tuma, Havner and French (12). Single panel

solutions were extended by the method of moment distribution to the analysis of two-way continuous rectangular plates supported by beams with flexural and torsional rigidities by Ang and Newmark (13).

1.2. Scope of Study. This study extends the flexibility method of approach to the solution of rectangular plates continuous in two directions and supported by flexible beams. Torsional stiffness of the beams is not taken into consideration because of the complex nature of the problem.

The essentials of the flexibility approach to continuous rectangular plates were discussed by Tuma in a graduate course in plate structures during fall 1961-1962. A rectangular plate supported by four columns at corners and having all edges free, is selected as a basic structure. A method of obtaining influence coefficients for deflection for the selected basic structure is described in Chapter II. In Chapter III general moment and reaction equations are derived in terms of flexibilities from compatibility conditions at the junction of two adjacent panels, and a matrix formulation for the solution is presented. All the flexibilities are defined in terms of the influence coefficients for deflection in Chapter IV. An example problem is worked out in Chapter V and a summary and conclusions are given in Chapter VI.

## CHAPTER II

### DEFLECTION INFLUENCE COEFFICIENTS BY FINITE DIFFERENCES

2.1. General Finite Difference Equation. Consider a thin rectangular plate subjected to normal loads and supported by four columns at the four corners (Figure 2.1).

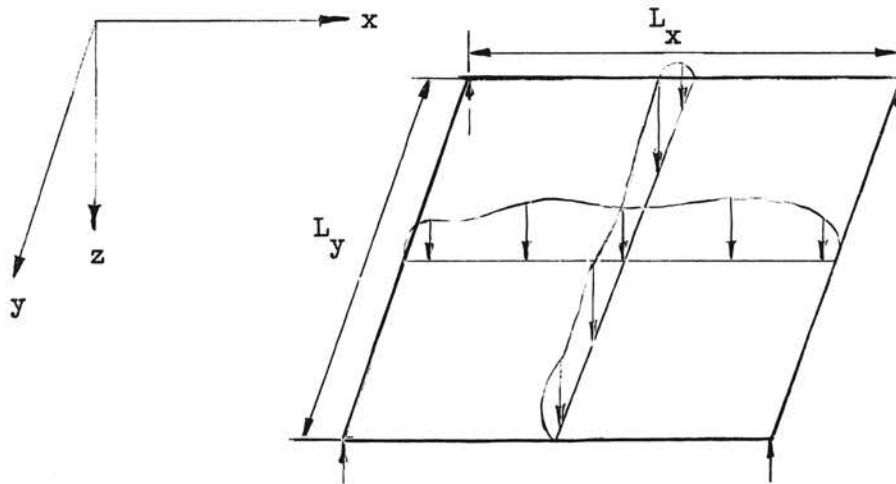


Figure 2.1. Basic Plate Structure

With usual assumptions, the deflections are governed by Lagrange's differential equation:

$$\frac{\partial^4 w}{\partial x^4} + 2 \frac{\partial^4 w}{\partial x^2 \partial y^2} + \frac{\partial^4 w}{\partial y^4} = \frac{p}{D} \quad (2.1)$$

where,

$x, y$  = Coordinates of a point on the plate surface.

$w$  = Deflection at any point  $x, y$ .

$p$  = Intensity of loading at the point.

$D$  = Flexural rigidity of the plate.

Equation 2.1 can be resolved into two equations:

$$\frac{\partial^2 M}{\partial x^2} + \frac{\partial^2 M}{\partial y^2} = -p \quad (2.2)$$

$$\frac{\partial^2 w}{\partial x^2} + \frac{\partial^2 w}{\partial y^2} = -\frac{M}{D} \quad (2.3)$$

where,

$$M = -D \left( \frac{\partial^2 w}{\partial x^2} + \frac{\partial^2 w}{\partial y^2} \right)$$

Consider that the plate structure shown in Figure 2.1 is divided into an arbitrary number of equal size rectangular elements  $\Delta x$  and  $\Delta y$  along  $x$  and  $y$ -axes. A typical detail of gridwork thus formed is shown in Figure 2.2.

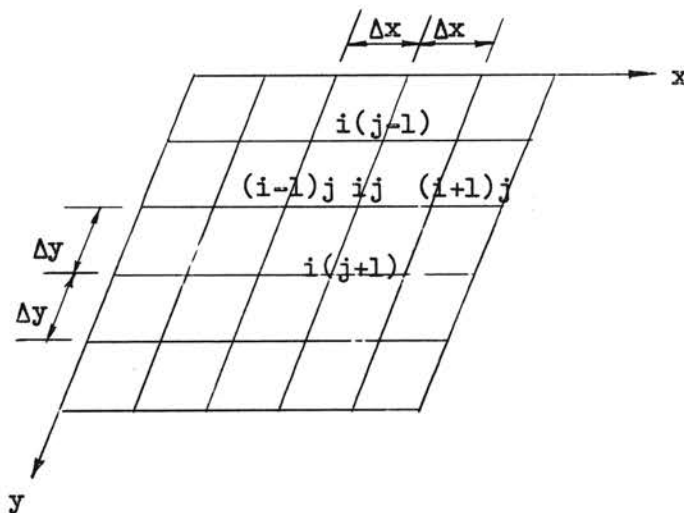


Figure 2.2. Grid Network

Expressing Equations 2.2 and 2.3 in finite difference form at any general point  $ij$ ,

$$\frac{M_{(i+1)j} - 2M_{ij} + M_{(i-1)j}}{\Delta x^2} + \frac{M_{i(j+1)} - 2M_{ij} + M_{i(j-1)}}{\Delta y^2} = -p_{ij} \quad (2.4)$$

$$\frac{w_{(i+1)j} - 2w_{ij} + w_{(i-1)j}}{\Delta x^2} + \frac{w_{i(j+1)} - 2w_{ij} + w_{i(j-1)}}{\Delta y^2} = -\frac{M_{ij}}{D} \quad (2.5)$$

With the following notation

$$t = \frac{\Delta x}{\Delta y}, \quad a = \frac{1}{2(1+t^2)}, \quad b = \frac{t^2}{2(1+t^2)}$$

$$\lambda = \frac{t}{2(1+t^2)} \quad \text{and} \quad \Delta A = \Delta x \cdot \Delta y$$

the above equations reduce to

$$M_{ij} - a(M_{(i+1)j} + M_{(i-1)j}) - b(M_{i(j+1)} + M_{i(j-1)}) = p_{ij} \lambda \Delta A \quad (2.6)$$

$$w_{ij} - a(w_{(i+1)j} + w_{(i-1)j}) - b(w_{i(j+1)} + w_{i(j-1)}) = \frac{M_{ij}}{D} \lambda \Delta A \quad (2.7)$$

If Equation 2.7 is written at points  $(i+1)j$ ,  $(i-1)j$ ,  $i(j+1)$  and  $i(j-1)$  successively, the following equations will result:

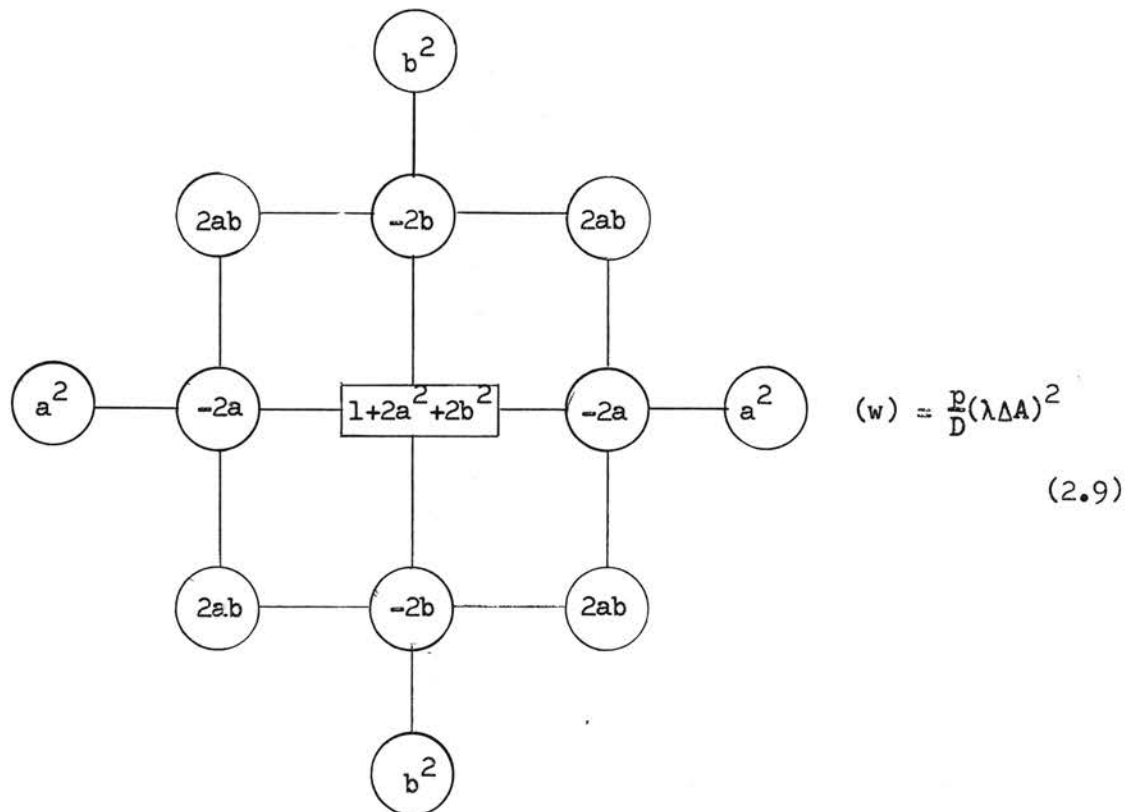
$$\frac{M_{(i+1)j}}{D} \lambda \Delta A = w_{(i+1)j} - a(w_{(i+2)j} + w_{ij}) - b(w_{(i+1)(j+1)} + w_{(i+1)(j-1)})$$

$$\frac{M_{(i-1)j}}{D} \lambda \Delta A = w_{(i-1)j} - a(w_{ij} + w_{(i-2)j}) - b(w_{(i-1)(j+1)} + w_{(i-1)(j-1)})$$

$$\frac{M_{i(j+1)}}{D} \lambda \Delta A = w_{i(j+1)} - a(w_{(i+1)(j+1)} + w_{(i-1)(j+1)}) - b(w_{i(j+2)} + w_{ij})$$

$$\frac{M_i(j-1)}{D} \lambda \Delta A = w_{i(j-1)} - a \left( w_{(i+1)(j-1)} + w_{(i-1)(j-1)} \right) - b \left( w_{ij} + w_{i(j+2)} \right) \quad (2.8)$$

Substituting Equations 2.7 and 2.8 in Equation 2.6, Lagrange's equation is obtained in finite difference form which can be represented as,



This equation is valid for all the points lying in the rectangle formed by second interior lines from the edges.

## 2.2. Finite Difference Equations for Typical Points Near the Edges.

The general finite difference equation will be modified for various points near the edges as follows:

- (a) Point on First Interior Line parallel to the y-axis

(Figure 2.3a).

The boundary condition is

$$(M_x)_{\text{edge}} = -D \left( \frac{\partial^2 w}{\partial x^2} + \nu \frac{\partial^2 w}{\partial y^2} \right) = 0$$

$$\text{or } (M)_{\text{edge}} = -D (1-\nu) \frac{\partial^2 w}{\partial y^2}$$

Applying this condition to the point  $(i-1)j$

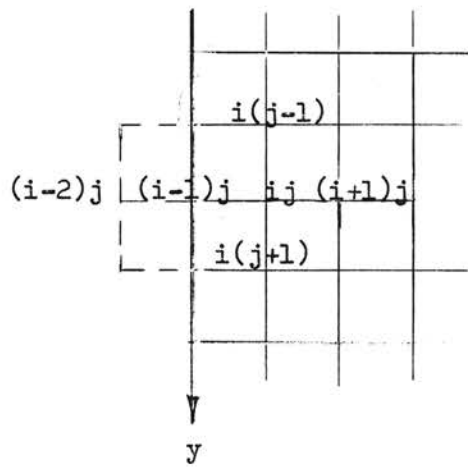
$$\frac{M_{(i-1)j}}{D} = -\frac{1-\nu}{\Delta y^2} \left( w_{(i-1)(j-1)} - 2w_{(i-1)j} + w_{(i-1)(j+1)} \right)$$

$$\text{Denoting } \frac{1-\nu}{(\Delta y)^2} \lambda \Delta A = (1-\nu) \lambda t = d$$

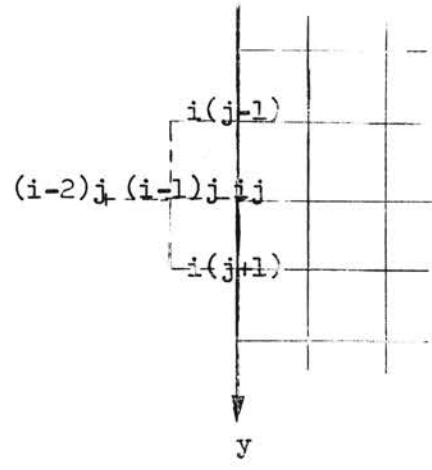
the equation can be written as

$$\frac{M_{(i-1)j}}{D} \lambda \Delta A = -d \left( w_{(i-1)(j-1)} - 2w_{(i-1)j} + w_{(i-1)(j+1)} \right) \quad (2.10)$$

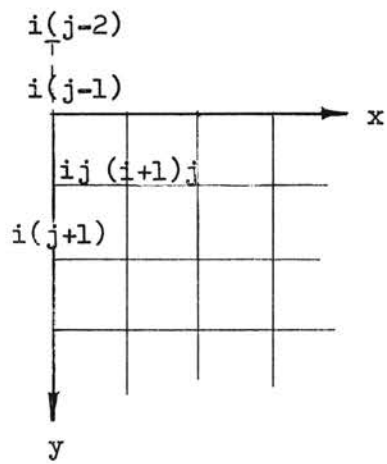
Substituting this in Equation 2.6 along with Equations 2.7 and 2.8,



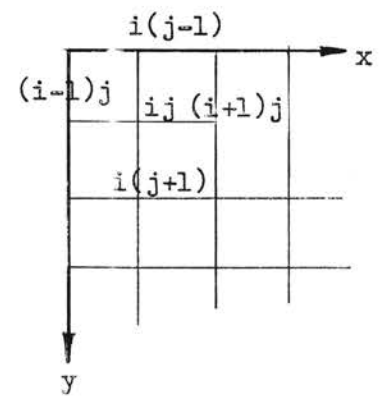
(a)



(b)



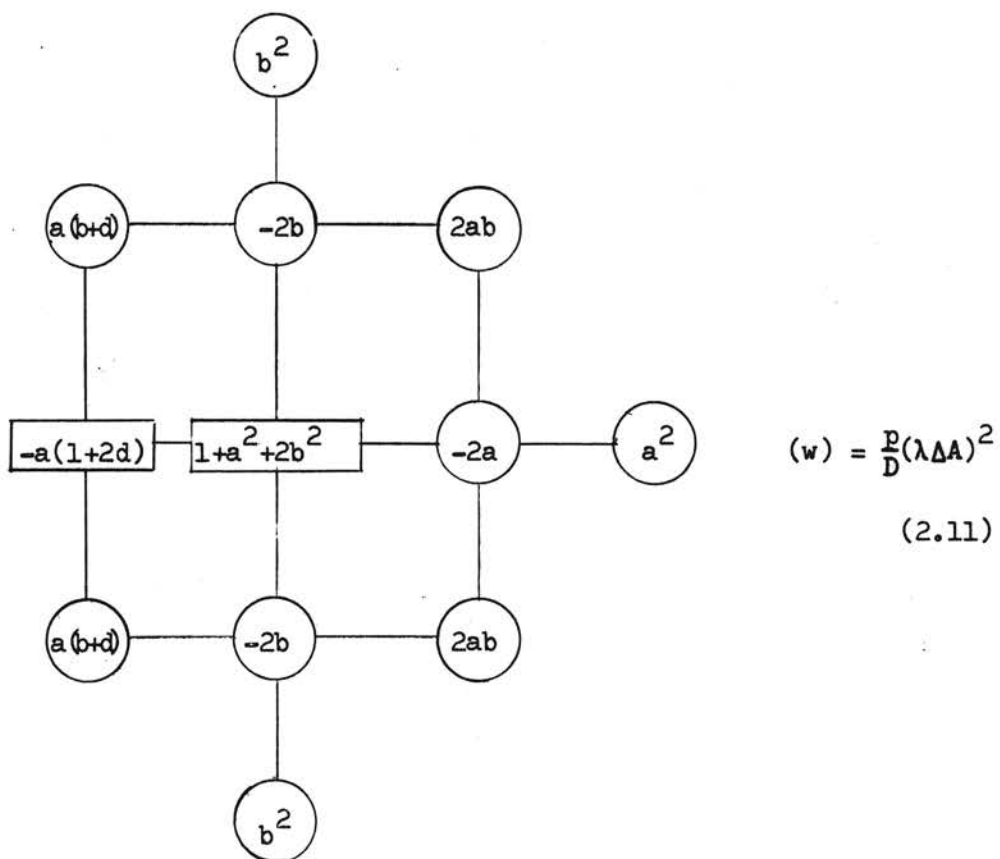
(c)



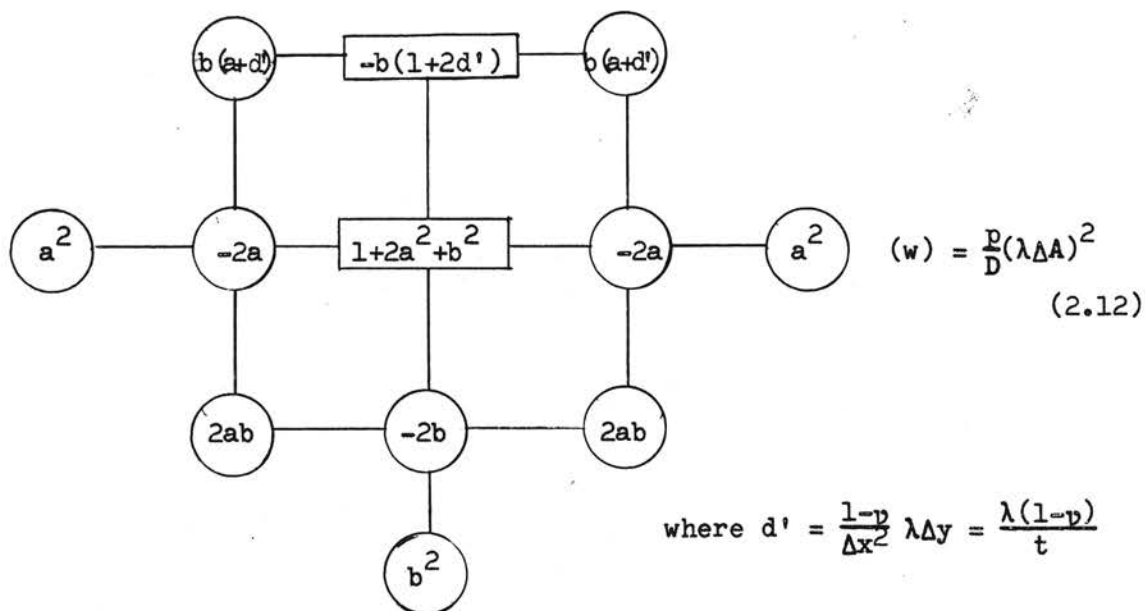
(d)

Figure 2.3. Typical Points Near the Edges





If the point lies on the first interior point parallel to the x-axis this equation modifies to



(b) Point on the Free Edge parallel to the  $y$ -axis (Figure 2.3b).

When point  $ij$  falls on the edge, points  $(i-2)j$ ,  $(i-1)j$ ,  $(i-1)(j-1)$  and  $(i-1)(j+1)$  lie outside the plate. The deflections at these points are expressed in terms of the deflections at the points on the plate by making use of the boundary conditions:

The first boundary condition is

$$(M_x)_{\text{edge}} = 0 \text{ or } (M)_{\text{edge}} = -D(1-\nu)\frac{\partial^2 w}{\partial y^2}.$$

In finite difference form this becomes,

$$\begin{aligned} \frac{M_x \lambda \Delta A}{D} &= w_{ij} -a(w_{(i+1)j} + w_{(i-1)j}) -b(w_{i(j+1)} + w_{i(j-1)}) \\ &= -d(w_{i(j-1)} -2w_{ij} + w_{i(j+1)}) \end{aligned}$$

from which

$$w_{(i-1)j} = w_{ij} \frac{(1-2d)}{a} + \frac{(d-b)}{a} (w_{i(j+1)} + w_{i(j-1)}) - w_{(i+1)j} \quad (2.13)$$

Similarly, expressing the same boundary condition at points  $i(j+1)$  and  $i(j-1)$ :

$$w_{(i-1)(j+1)} = w_{i(j+1)} \frac{(1-2d)}{a} + \frac{(d-b)}{a} (w_{ij} + w_{i(j+2)}) - w_{(i+1)(j+1)} \quad (2.14)$$

$$w_{(i-1)(j-1)} = w_{i(j-1)} \frac{(1-2d)}{a} + \frac{(d-b)}{a} (w_{ij} + w_{i(j-2)}) - w_{(i+1)(j-1)} \quad (2.15)$$

The second boundary condition is

$$R_x = -D \left( \frac{\partial^3 w}{\partial x^3} + (2-\nu) \frac{\partial^3 w}{\partial x \partial y^2} \right) = 0.$$

Expressing this in finite difference form

$$\frac{1}{2\Delta x^2} \left( w_{(i+2)j} - 2w_{(i+1)j} + 2w_{(i-1)j} - w_{(i-2)j} \right) + \frac{2-\nu}{2\Delta x\Delta y^2} \left( w_{(i+1)(j+1)} - w_{(i-1)(j+1)} - 2w_{(i+1)j} + 2w_{(i-1)j} - w_{(i-1)(j-1)} + w_{(i+1)(j-1)} \right) = 0 .$$

Solving for  $w_{(i-2)j}$  ,

$$w_{(i-2)j} = w_{(i+2)j} - 2w_{(i+1)j} + 2w_{(i-1)j} + c \left( w_{(i+1)(j+1)} - w_{(i-1)(j+1)} - 2w_{(i+1)j} + 2w_{(i-1)j} - w_{(i-1)(j-1)} + w_{(i+1)(j-1)} \right) \quad (2.16)$$

where  $c = (2-\nu)t^2$

The unknown values  $w_{(i-1)j}$  ,  $w_{(i-1)(j+1)}$  and  $w_{(i-1)(j-1)}$  can be eliminated from the above equation by using Equations 2.13, 2.14 and 2.15.

Substituting Equations 2.13 to 2.16 in the general equation (2.9), the operator equation obtained is

$$\begin{array}{c}
 \boxed{b^2 - (d-b)(2b-ac)} \\
 | \\
 \boxed{-2b+2(d-b)(a+ac-1) + (1-2d)(2b-ac)} \quad \text{---} \quad \textcircled{2a^2c} \\
 | \\
 \boxed{1+2a^2+2b^2+2(1-2d)(a+ac-1) + 2(d-b)(2b-ac)} \quad \text{---} \quad \boxed{-4a^2(1+c)} \quad \text{---} \quad \textcircled{2a^2} \\
 | \\
 \boxed{-2b+2(d-b)(a+ac-1) + (1-2d)(2b-ac)} \quad \text{---} \quad \textcircled{2a^2c} \\
 | \\
 \boxed{b^2 - (d-b)(2b-ac)}
 \end{array}
 \quad (w) = \frac{p}{2D} (\lambda \Delta \Delta)^2 \quad (2.17)$$

If the point lies on the free edge parallel to the  $x$ -axis, the equation modifies to

$$\begin{array}{c}
 \boxed{a^2 - (d'-a)(2a-bc')} \quad \text{---} \quad \boxed{-2a+2(d'-a)(b+bc'-1) + (1-2d')(2a-bc')} \quad \text{---} \quad \boxed{1+2a^2+2b^2+(1-2d')(b+bc'-1) + 2(d'-a)(2a-bc')} \quad \text{---} \quad \boxed{-2a+2(d'-a)(b+bc'-1) + (1-2d')(2a-bc')} \quad \text{---} \quad \boxed{a^2 - (d'-a)(2a-bc')} \\
 | \quad \quad \quad | \quad \quad \quad | \quad \quad \quad | \\
 \textcircled{2b^2c'} \quad \text{---} \quad \boxed{-4b^2(1+c')} \quad \text{---} \quad \textcircled{2b^2c'} \\
 | \\
 \textcircled{2b^2}
 \end{array}
 \quad (w) = \frac{p}{2D} \lambda (\Delta \Delta)^2 \quad (2.18)$$

where  $d' = \frac{(1-\nu)}{t}$  and  $c' = \frac{(2-\nu)}{t^2}$

- (c) Point adjacent to a support on the Free Edge parallel to the  $y$ -axis (Figure 2.3c).

The boundary conditions are:

$$(i) \quad w_i(j-1) = 0 \quad (2.19)$$

$$(ii) (M_x)_{i(j-1)} = (M_y)_{i(j-1)} = 0$$

From which it follows that

$$w_{(i-2)j} = -w_{ij} \quad (2.20)$$

Substituting in Equation 2.17,

$$(w) = \frac{p}{2D} (\lambda \Delta \Delta)^2 \quad (2.21)$$

If the point is adjacent to a support on the free edge parallel to the x-axis, the above equation takes the form,

$$(w) = \frac{p}{2D} (\lambda \Delta \Delta)^2 \quad (2.22)$$

(d) First Interior Corner Point (Figure 2.3d).

The boundary conditions are:

$$(i) \quad w_{(i-1)(j-1)} = 0$$

$$(ii) \quad (M_x)_{(i-1)j} = (M_y)_{i(j-1)} = 0$$

Applying this condition at points  $(i-1)j$  and  $i(j-1)$ ,

$$\left. \begin{aligned} \frac{M_{(i-1)j}}{D} \lambda \Delta A &= -d \left( w_{(i-1)(j+1)} - 2w_{(i-1)j} + w_{(i-1)(j-1)} \right) \\ \frac{M_{i(j-1)}}{D} \lambda \Delta A &= -d' \left( w_{(i+1)(j-1)} - 2w_{i(j-1)} + w_{(i-1)(j-1)} \right) \end{aligned} \right\} (2.23)$$

Substituting Equations 2.23 along with Equations 2.7 and 2.8 in 2.6,

$$(w) = \frac{P}{D} (\lambda \Delta A)^2 \quad (2.24)$$

2.3. Deflection Influence Coefficients. The deflection at a point  $ij$  due to a unit load at point  $kl$  is defined as "Deflection Influence Coefficient" and is denoted by  $\eta_{ij}^{kl}$ . The deflections at all network points of the basic plate structure shown in Figure 2.1, due to a unit load at any point  $kl$ , can be determined by writing the equations derived in previous sections at various points and solving them simultaneously. A matrix formulation and computer solution is very convenient in such cases. Using the abbreviated notation, the matrix formulation takes the form

$$\begin{bmatrix} A \end{bmatrix} \begin{bmatrix} w \end{bmatrix} = \begin{bmatrix} p \end{bmatrix} \quad (2.25)$$

where

$\begin{bmatrix} A \end{bmatrix}$  = Coefficient matrix

$\begin{bmatrix} w \end{bmatrix}$  = Deflection matrix

$\begin{bmatrix} p \end{bmatrix}$  = Load matrix

From Equation 2.25

$$\begin{bmatrix} w \end{bmatrix} = \begin{bmatrix} A \end{bmatrix}^{-1} \begin{bmatrix} p \end{bmatrix} \quad (2.26)$$

Thus the deflection influence coefficients due to unit load at  $k1$  can readily be obtained by inverting the coefficient matrix  $A$  by means of a computer and post multiplying it by load matrix  $p$  which has unity as the element corresponding to  $k1$ , the remaining elements being zero.

If  $\eta_{ij}^{k1}$  is the deflection influence coefficient as defined above, the deflection at  $ij$  due to a unit load at  $k1$  becomes

$$w_{ij}^{k1} = \frac{\Delta x \Delta y}{D} \eta_{ij}^{k1} \quad (2.27)$$

The deflection influence coefficients due to unit load at other points can be obtained by changing the elements of matrix  $p$  successively and pre-multiplying by  $\begin{bmatrix} A \end{bmatrix}^{-1}$ .

If the computer being utilized has internal storage capable of directly inverting a matrix of order 'n' and if the order of matrix  $A$  exceeds this, a method which utilizes the geometric symmetry of the basic structure and the principle of superposition can be applied.

An unsymmetrically loaded symmetrical plate can be represented as the summation of four symmetrically and antisymmetrically loaded plates as shown in Figure 2.4.

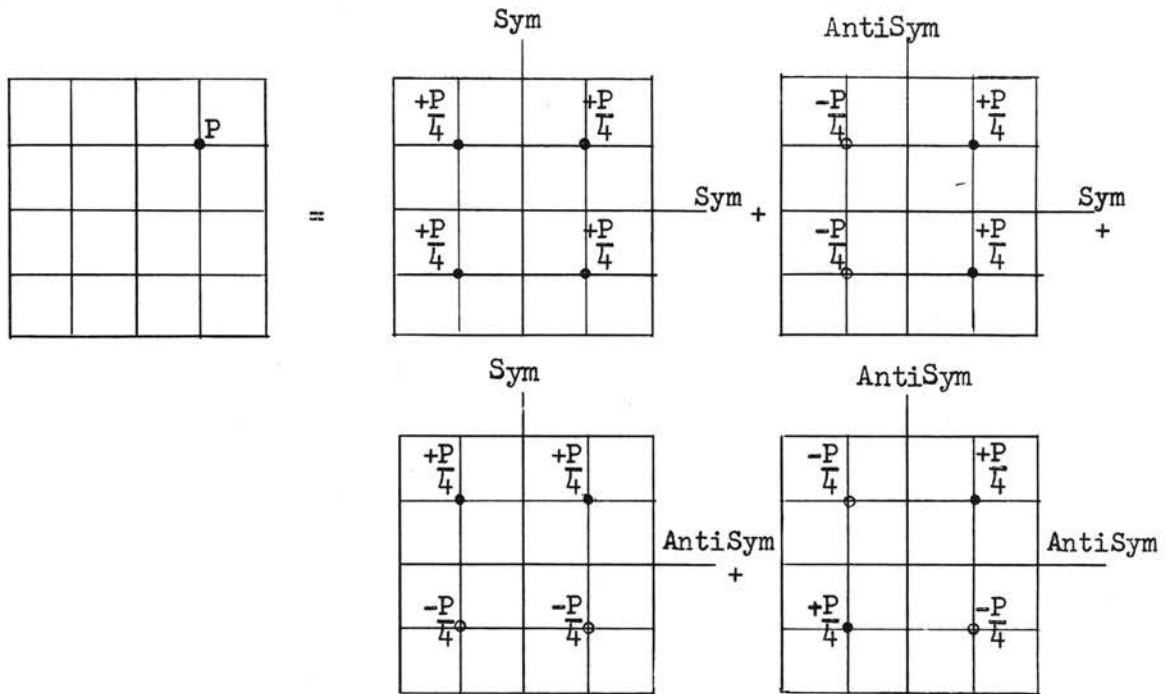


Figure 2.4. Resolution of Antisymmetrically Loaded Symmetrical Plate.

It can be easily seen that the deflections in the upper right quadrant are sufficient to determine the deflections throughout the entire plate in each of the four plates on the right side. When once the deflections throughout these plates are obtained, the deflections due to unsymmetrical load  $P$  on the plate on the left side can be obtained by the method of superposition. Thus, the problem reduces to inversion of matrices of much smaller order than  $A$ .



## CHAPTER III

### GENERAL MOMENT AND REACTION EQUATIONS

3.1. Derivation of Moment and Reaction Equations. A continuous rectangular plate subjected to loads normal to the middle plane of the plate is considered (Figure 3.1). The flexural rigidity in any panel is constant. The supporting beams are flexible and their torsional rigidity is neglected.

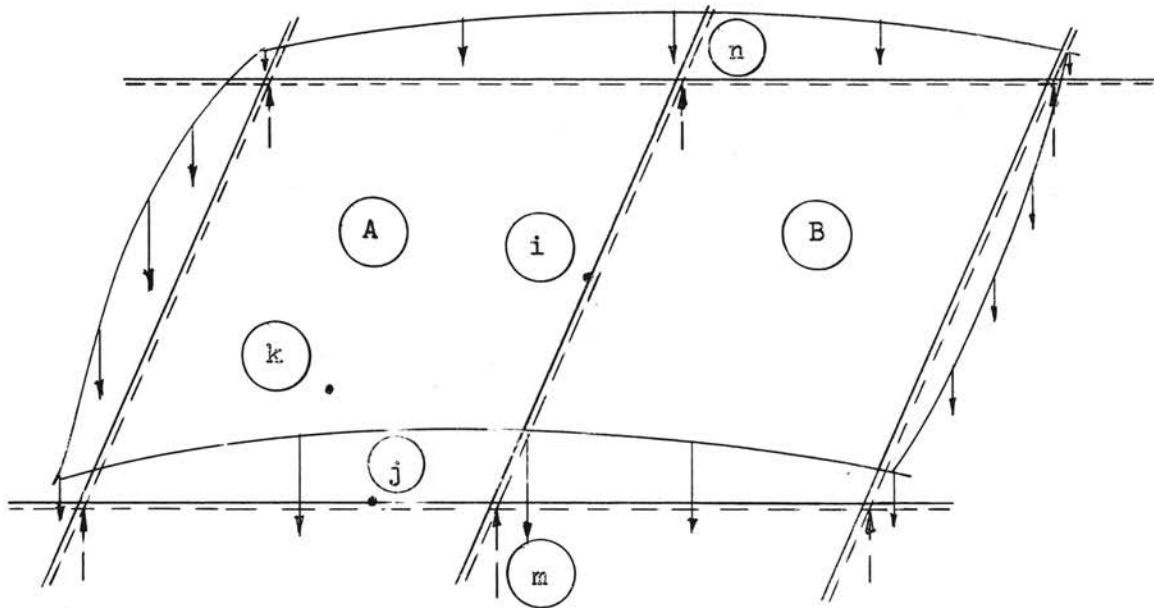


Figure 3.1. General Structure

There are three unknowns at any point along the common boundary of any two adjacent panels A and B. These are the moment and the two reactions between the panels and the beam. These can be obtained from the compatibility conditions:

- (i) The sum of the normal slopes of adjacent panels at any point along a supporting beam is zero.
- (ii) The displacement of each of the panels at any point along the beam must be equal to the displacement of the beam at that point.

If  $(\theta_i)_A$  and  $(\theta_i)_B$  are rotations at  $i$  of panels A and B, the first compatibility condition requires that (See Figure 3.2)

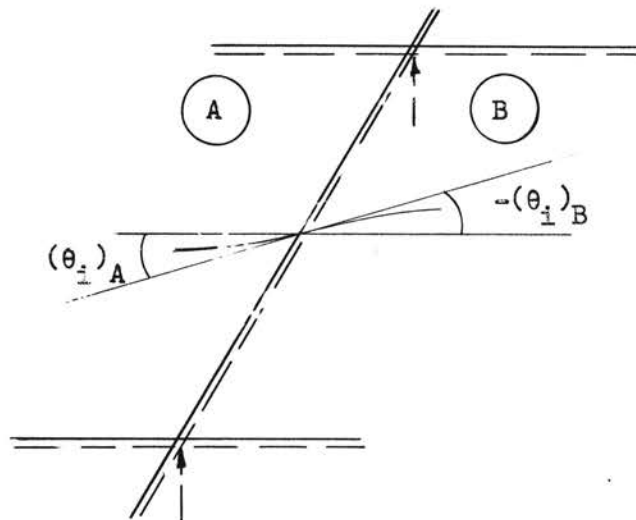


Figure 3.2. Slope Compatibility of Adjacent Panels

$$(\theta_i)_A + (\theta_i)_B = 0 \quad (3.1)$$

If  $(\Delta_i)_A$ ,  $(\Delta_i)_B$  and  $(\Delta_i)^{\text{Beam}}$  are the displacements at  $i$  of panels A, B and the supporting beam, respectively, the second compatibility condition requires that (Figure 3.3)

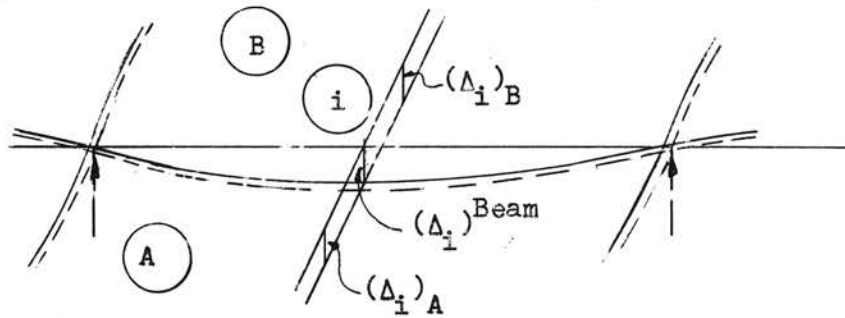


Figure 3.3. Displacement Compatibility

$$(\Delta_i)_A = (\Delta_i)^{\text{Beam}} \quad (3.2)$$

$$(\Delta_i)_B = (\Delta_i)^{\text{Beam}} \quad (3.3)$$

The algebraic expressions for the slopes and displacements are:

$$(\theta_i)_A = \sum_A \tau_{ik} P_k + (F_i)_A M_i + \sum_A G_{ij} M_j + (-T_i)' R_i + \sum_A (-Q_{ij})' R_j \quad (3.4)$$

$$(\theta_i)_B = \sum_B \tau_{ik} P_k + (F_i)_B M_i + \sum_B G_{ij} M_j + (-T_i)'' R_i + \sum_B (-Q_{ij})'' R_j \quad (3.5)$$

$$(\Delta_i)_A = \sum_A \delta'_{ik} P_k + (T_i)' M_i + \sum_A Q'_{ij} M_j + (-D_i)' R_i + \sum_A (-H_{ij})' R_j \quad (3.6)$$

$$(\Delta_i)_B = \sum_B \delta''_{ik} P_k + (T_i)'' M_i + \sum_B Q''_{ij} M_j + (-D_i)'' R_i + \sum_B (-H_{ij})'' R_j \quad (3.7)$$

$$(\Delta_i)^{\text{Beam}} = (\delta_i)^B + R_i D_i^B + \sum_{\text{Beam}} H_{ij}^B R_j + Q_{im}^B M_m + Q_{in}^B M_n \quad (3.8)$$

Where:

$j$  is any point, other than  $i$ , on the boundary of the panels.

$k$  is a typical interior point of the panels.

The angular load function  $\tau_{ik}$  is the edge slope at  $i$  due to a unit load at  $k$ , considering the plate as supported by columns only at the corners (hereafterwards referred to as "basic structure").

The displacement load function  $\delta_{ik}'$ , ( $\delta_{ik}''$ ) is the edge displacement at  $i$  of the basic structure A, (B) due to a unit shear at  $k$ .

The angular flexibility  $(F_i)_{A,B}$  is the edge slope at  $i$  of the basic structure A or B respectively due to a unit moment at  $i$ .

The angular-displacement flexibility  $T_i'$ , ( $T_i''$ ) is the edge displacement at  $i$  of the basic structure A, (B) due to a unit moment at  $i$ .

By virtue of Maxwell-Betti Reciprocal Theorem,  $T_i$  can also be defined as the edge slope at  $i$  due to a unit shear at  $i$ .

The angular carry-over  $G_{ij}$  is the edge slope at  $i$  of the basic structure due to a unit moment at  $j$ .

The angular-displacement carry-over  $Q_{ij}'$ , ( $Q_{ij}''$ ) is the edge deflection at  $i$  of the basic structure A (B) due to a unit moment at  $j$ .

From Maxwell-Betti Theorem  $Q_{ij}$  can also be defined as the slope at  $i$  due to a unit shear at  $j$ .

The displacement flexibility  $D_i'$  ( $D_i''$ ) is the edge displacement at  $i$  of the basic structure A (B) due to a unit shear at  $i$ .

The displacement carry-over  $H_{ij}'$ , ( $H_{ij}''$ ) is the edge slope at  $i$  of the basic structure A (B) due to a unit shear at  $j$ .

The displacement load function  $\delta_i^B$  is the displacement at  $i$  due to the weight of the beam.

The displacement flexibility  $D_i^B$  is the displacement at  $i$  of the beam  $mn$  due to a unit shear ' $i$ ', considering the beam to be simply supported.

The displacement-angular carry-over  $(Q_i)_{m,n}^B$  is the displacement at  $i$  of the beam  $mn$  due to a unit moment at  $m$  or  $n$  respectively, considering the beam to be simply supported.

The displacement carry-over  $H_{i,j}^B$  is the displacement at  $i$  of the beam  $mn$  due to a unit shear at any other point  $j$  on the beam.

$P_k$  is any load applied at  $k$ .

$M_i$  and  $M_j$  are the bending moments at  $i$  and  $j$  respectively.

$R_i'$  and  $R_i''$  are the reactions at  $i$  of the panels A and B respectively, assumed to be acting upwards (Figure 3.4).

$R_j'$  and  $R_j''$  are the reactions at  $j$  of the panels A and B respectively, assumed to be acting upwards.

$M_m^B$  and  $M_n^B$  are the moments at ends of the beam  $mn$ .

$R_i$  and  $R_j$  are the reactions on the beam  $mn$  at  $i$  and  $j$  assumed to be acting downwards (Figure 3.4).

A graphical illustration of the various angular and displacement functions is given in Chapter IV.

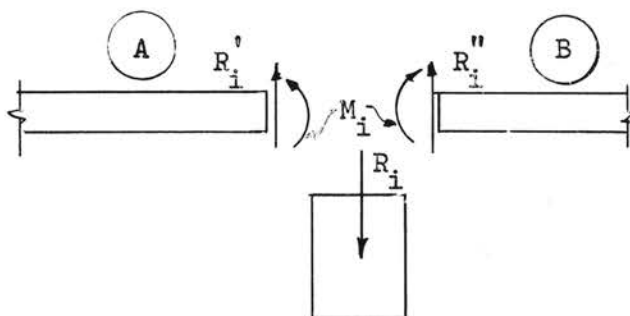


Figure 3.4. Reactions Between Plates and Supporting Beam

From Figure 3.4 it can be easily seen that

$$R_i = R_i' + R_i'' + q \quad (3.9)$$

where

$q$  is the weight of beam of length  $\Delta x$  or  $\Delta y$ .

Similarly,

$$R_j = R_j' + R_j'' + q \quad (3.10)$$

Substituting Equations 3.4 and 3.5 into 3.1, Equations 3.6, 3.7, 3.8, 3.9 and 3.10 into 3.2 and 3.3 the general moment and reaction equations are obtained:

$$\begin{aligned} \sum_{A,B} P_k \tau_{ik} + M_i \sum_{A,B} G_i + \sum_{A,B} M_j G_{ij} + R_i' (-T_i)_A + \sum_A (-Q_{ij}) R_j' + R_i'' (-T_i)_B + \\ + \sum_B (-Q_{ij}) R_j'' = 0 \end{aligned} \quad (3.11)$$

$$\begin{aligned} (\sum_A \delta_{ik} P_k + \delta_i^B) + M_i (T_i)_A + \sum_A Q_{ij} M_j - R_i' \{ (D_i)_A + D_i^F \} - R_i'' D_i^B - \sum_A H_{ij} R_j' - \\ - \sum_{Beam} H_{ij}^B R_j' - \sum_{Beam} R_j'' H_{ij}^B - M_m^Q{}^B - M_n^Q{}^B = 0 \end{aligned} \quad (3.12)$$

$$\begin{aligned} (\sum_B \delta_{ik} P_k + \delta_i^B) + M_i (T_i)_B + \sum_B Q_{ij} M_j - R_i' \{ (D_i)_B + D_i^B \} - R_i'' D_i^B - \sum_B H_{ij} R_j' - \\ - \sum_{Beam} H_{ij}^B R_j' - \sum_{Beam} R_j'' H_{ij}^B - M_m^Q{}^B - M_n^Q{}^B = 0 \end{aligned} \quad (3.13)$$

The moments  $M_m$  and  $M_n$  can be determined from the continuity condition of the supporting beam. Two isolated spans of a continuous supporting beam loaded by reactions from the plate are shown in Figure 3.5.

Using the flexibility method of analysis of continuous beams (14), the three moment equation is

$$\sum_{lm,mn} \tau_m^B + M_m (F_{ml}^B + F_{mn}^B) + M_l G_{ml}^B + M_n G_{mn}^B + \sum_{lm,mn} R_i Q_{mi}^B = 0 \quad (3.14)$$

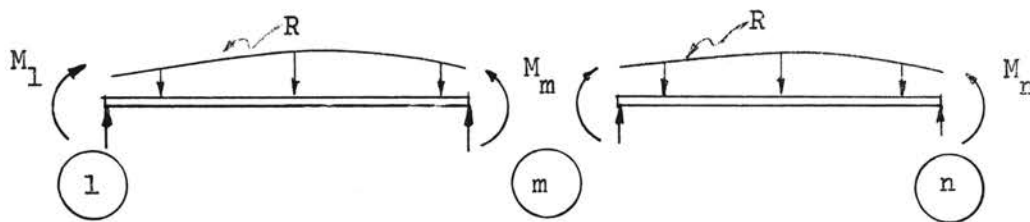


Figure 3.5. Continuous Supporting Beam

where

Angular load function  $\tau_m^B$  is the slope at  $m$  of the beam  $mn$  due to its weight.

Angular flexibility  $F_{mn}^B$  (or  $F_{mi}^B$ ) is the slope of the beam  $mn$  (or  $lm$ ) at  $m$  due to a unit moment at  $m$ .

Angular carry-over  $G_{mn}$  (or  $G_{ml}$ ) is the slope of  $m$  at the beam  $mn$  (or  $lm$ ) due to a unit moment at  $n$  (or  $l$ ).

The displacement-angular carry-over  $Q_{mi}$  is the end slope at  $m$  due to unit shear  $i$ .

As many such equations as the number of continuous supports can be written for each supporting continuous beam. Equations thus obtained, when combined with those obtained by writing Equations 3.11, 3.12 and 3.13 at various points along the boundaries of continuous plate panels, yield the complete solution of the problem.

A digital computer solution suggests itself because of the large number of unknowns involved. A matrix from the above general moment and reaction equations can be formulated as follows:

$$\begin{bmatrix} \Sigma \tau_1 P_k \\ \Sigma \tau_2 P_k \\ \cdot \\ \Sigma \tau_s P_k \\ \Sigma \delta_1 P_k \\ \Sigma \delta_2 P_k \\ \cdot \\ \Sigma \delta_s P_k \\ \Sigma \tau_m^B \\ \Sigma \tau_n^B \\ \cdot \\ \Sigma \tau_r^B \end{bmatrix} + \begin{bmatrix} \Sigma F_1 & G_{12} & \cdot & \cdot & G_{1s} & T_1 & Q_{12} & \cdot & \cdot & Q_{1s} & 0 & \cdot & \cdot & 0 \\ G_{21} & \Sigma F_1 & \cdot & \cdot & G_{2s} & Q_{21} & T_2 & \cdot & \cdot & Q_{2s} & 0 & \cdot & \cdot & 0 \\ \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot \\ G_{s1} & G_{s2} & \cdot & \cdot & \Sigma F_s & Q_{s1} & Q_{s2} & \cdot & \cdot & T_s & 0 & \cdot & \cdot & \cdot \\ T_1 & Q_{12} & \cdot & \cdot & Q_{1s} & \Sigma D_1 & H_{12} & \cdot & \cdot & H_{1s} & Q_{m1}^B & Q_{n1}^B & 0 & 0 \\ Q_{21} & T_2 & \cdot & \cdot & Q_{2s} & H_{21} & \Sigma D_2 & \cdot & \cdot & H_{2s} & Q_{2m}^B & Q_{2n}^B & 0 & 0 \\ \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot \\ Q_{s1} & Q_{s2} & \cdot & \cdot & T_s & H_{s1} & H_{s2} & \cdot & \cdot & \Sigma D_s & \cdot & \cdot & \cdot & Q_{sr} \\ 0 & 0 & \cdot & \cdot & 0 & Q_{m1}^B & Q_{m2}^B & \cdot & \cdot & Q_{ms}^B & \Sigma F_m^B & G_{mn} & 0 & 0 \\ 0 & 0 & \cdot & \cdot & 0 & Q_{n1}^B & Q_{n2}^B & \cdot & \cdot & Q_{ns}^B & G_{nm} & \Sigma F_n & 0 & 0 \\ \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot \\ 0 & 0 & \cdot & \cdot & 0 & Q_{r1}^B & Q_{r2}^B & \cdot & \cdot & Q_{rs}^B & \cdot & \cdot & \cdot & \Sigma F_r \end{bmatrix} \begin{bmatrix} M_1 \\ M_2 \\ \cdot \\ M_s \\ -R_1 \\ -R_2 \\ \cdot \\ -R_s \\ -M_m^B \\ -M_n^B \\ \cdot \\ -M_r^B \end{bmatrix} = 0 \quad (3.15)$$

The General Moment and Reaction Matrix Equation



where the subscript  $s$  corresponds to the total number of boundary points.  $M_m, M_n$ , etc. are the moments in the beam over the supports.

The solution can be obtained by inverting the coefficient matrix, as already explained in Chapter II.

In case the unknown moments and reactions are too many to be handled by the computer, they can be reduced by adopting the following matrix reduction.

Using abbreviated notation, the general moment and reaction matrix can be written as,

$$\begin{bmatrix} [G] & [Q] \\ [Q] & [H] & [Q^B] \\ & [Q^B] & [G^B] \end{bmatrix} \begin{bmatrix} [M] \\ [-R] \\ [-M^B] \end{bmatrix} = - \begin{bmatrix} [\tau] \\ [\delta] \\ [\tau^B] \end{bmatrix} \quad (3.16)$$

where

$[G]$  and  $[G^B]$  are the submatrices of the angular functions of the plate and beam, respectively.

$[Q]$  and  $[Q^B]$  are the submatrices of the angular-displacement carry-overs of the plate and beam, respectively.

$[H]$  is the submatrix of the displacement functions of the plate and beam.

$[M]$  is the submatrix of the moments in the plate over the continuous supports.

$[R]$  is the submatrix of the reactions between the plate and supporting beams.

$[M^B]$  is the submatrix of the moments in the beam over the supports.

$[\tau]$  and  $[\tau^B]$  are the submatrices of the angular load functions of the plate and beam, respectively.

$[\delta]$  is the submatrix of the displacement load functions of the plate and beam.

Resolving Equation 3.15 into three equations,

$$[G] [M] - [Q] [R] = - [\tau] \quad (3.17)$$

$$[Q] [M] - [H] [R] - [Q^B] [M^B] = - [\delta] \quad (3.18)$$

$$- [Q^B] [R] - [G^B] [M^B] = - [\tau^B] \quad (3.19)$$

Solving for  $[M]$

$$[M] = - [G^B]^{-1} [\tau] + [G]^{-1} [Q] \cdot$$

$$\begin{aligned} & \left[ \left[ [Q]^{-1} [Q^B] \right]^{-1} \left( [Q]^{-1} [H] - [G]^{-1} [Q] \right) - [G^B]^{-1} [Q^B] \right]^{-1} \cdot \\ & \left[ \left[ [Q]^{-1} [Q^B] \right]^{-1} \left( [Q]^{-1} [\delta] - [G]^{-1} [\tau] \right) - [G^B]^{-1} [\tau^B] \right] \end{aligned} \quad (3.20)$$

Thus by successive inversions and other algebraic operations of coefficient submatrices, the moments can be evaluated. The values of  $[R]$  and  $[M^B]$  are obtained as

$$[R] = [Q]^{-1} [\tau] + [Q]^{-1} [G] [M] \quad (3.21)$$

$$[M^B] = [G^B]^{-1} [\tau^B] - [G^B]^{-1} [Q^B] [R] \quad (3.22)$$

Thus the remaining unknowns  $[R]$  and  $[M^B]$  can be determined successively from  $[M]$ .

## CHAPTER IV

### ANGULAR AND DISPLACEMENT FUNCTIONS

4.1. Angular and Displacement Load Functions. Consider a rectangular plate supported by columns at the corners to be acted upon by a load  $P = 1$  at point  $k$  (Figure 4.1). From the definitions given in the previous chapter, the slope of the deflection curve at  $i$  due to  $P_k = 1$  is the angular load function  $\tau_{ik}$  and the displacement at  $i$  due to  $P_k = 1$  is the displacement load function  $\delta_{ik}$ .

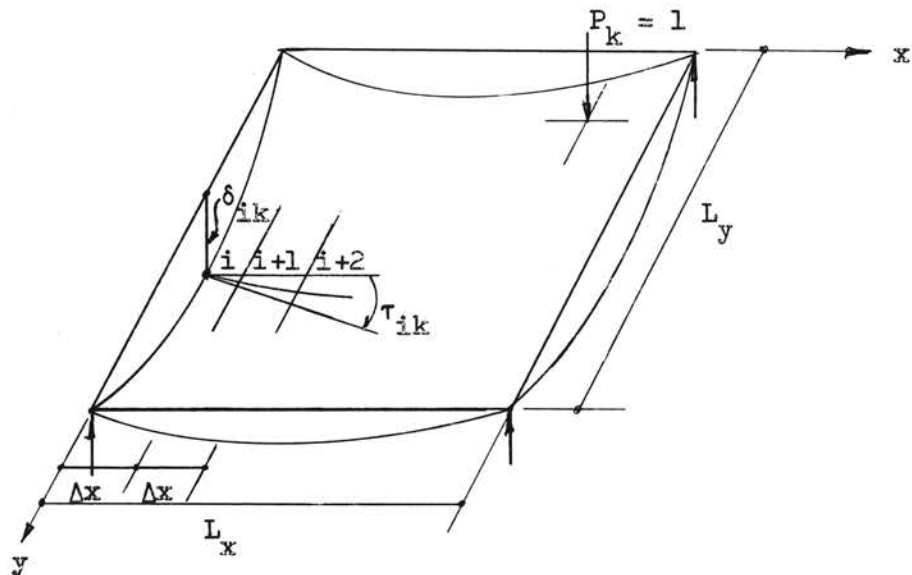


Figure 4.1. Angular Load and Displacement Functions

If the plate is divided into an arbitrary number of equally sized rectangular elements with sides  $\Delta x$  and  $\Delta y$  in the directions  $x$  and  $y$  respectively, the slope of deflection curve at 'i' can be approximated as:

$$\theta_i = \frac{w_{i+1} - w_i}{\Delta x} \quad (4.1)$$

where

$w_{i+1}$  and  $w_i$  are displacements at points  $i+1$  and  $i$ .

If  $\eta_{(i+1)k}$  and  $\eta_{ik}$  are the influence coefficients for the displacements at  $i+1$  and  $i$  respectively due to unit load at  $k$ ,

$$w_{(i+1)k} = \frac{1}{D} \Delta x \Delta y \eta_{(i+1)k} \quad (4.2)$$

$$w_{ik} = \frac{1}{D} \Delta x \Delta y \eta_{ik} \quad (4.3)$$

where

$D$  is the flexural rigidity of the plate.

From Equations 4.2 and 4.3

$$\tau_{ik} = \frac{\Delta x \Delta y}{D} \frac{1}{\Delta x} (\eta_{(i+1)k} - \eta_{ik})$$

or

$$\tau_{ik} = \frac{\Delta y}{D} (\eta_{(i+1)k} - \eta_{ik}) \quad (4.4)$$

and

$$\delta_{ik} = \frac{\Delta x \Delta y}{D} \eta_{ik} \quad (4.5)$$

If  $i$  is on edge parallel to the  $x$ -axis,

$$\tau_{ik} = \frac{\Delta x}{D} (\eta_{(i+1)k} - \eta_{ik}) \quad (4.6)$$

4.2. Angular and Angular-Displacement Flexibilities. Consider a rectangular plate supported by columns at the corners, to be acted upon by a unit moment at point  $i$  (Figure 4.2). From the definitions given in

the previous chapter, the rotation and displacement at  $i$  due to  $M_i = 1$  are angular and angular-displacement flexibilities  $F_i$  and  $T_i$  respectively.

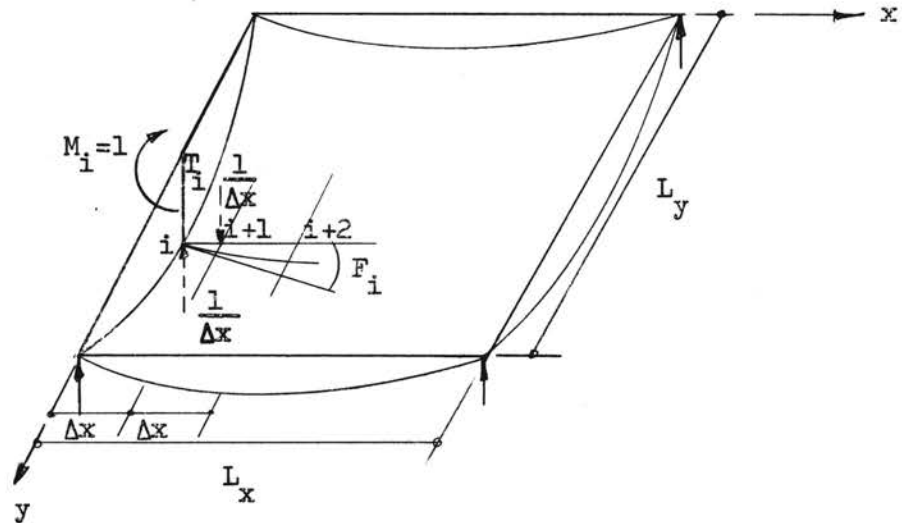


Figure 4.2. Angular and Angular-Displacement Flexibilities

The moment can be replaced by a couple with forces  $\frac{1}{\Delta x}$  at  $i$  and  $i+1$  as shown with dotted lines in Figure 3.2. From the definition of the influence coefficients for the displacement,

$$F_i = \frac{w_{i+1} - w_i}{\Delta x} = \frac{\Delta x \Delta y}{D} \frac{1}{(\Delta x)^2} \left\{ \left( \eta_{(i+1)(i+1)} - \eta_{(i+1)i} \right) - \left( \eta_{i(i+1)} - \eta_{ii} \right) \right\}.$$

But from Maxwell's Reciprocal Theorem,  $\eta_{(i+1)i} = \eta_{i(i+1)}$ . Therefore, the above equation can be written as:

$$F_i = \frac{1}{D} \frac{\Delta y}{\Delta x} \left\{ \eta_{(i+1)(i+1)} - 2\eta_{i(i+1)} + \eta_{ii} \right\} \quad (4.7)$$

From the discussion above, it follows that

$$T_i = \frac{\Delta x \Delta y}{D} \frac{1}{\Delta x} (\eta_{i(i+1)} - \eta_{ii})$$

or

$$T_i = \frac{\Delta y}{D} (\eta_{i(i+1)} - \eta_{ii}) \quad (4.8)$$

If  $i$  is on edge parallel to  $x$ -axis,

$$F_i = \frac{1}{D} \frac{\Delta x}{\Delta y} \{ \eta_{(i+1)(i+1)} - 2\eta_{i(i+1)} + \eta_{ii} \} \quad (4.9)$$

$$T_i = \frac{\Delta x}{D} (\eta_{i(i+1)} - \eta_{ii}) \quad (4.10)$$

4.3. Angular and Angular-Displacement Carry-Overs. Consider a column supported rectangular plate to be acted upon by a unit moment at  $j$  (Figure 4.3). From the definitions, the rotation and displacement at  $i$  due to  $M_j = 1$  are the angular and angular-displacement carry-overs  $G_{ij}$  and  $Q_{ij}$  respectively.

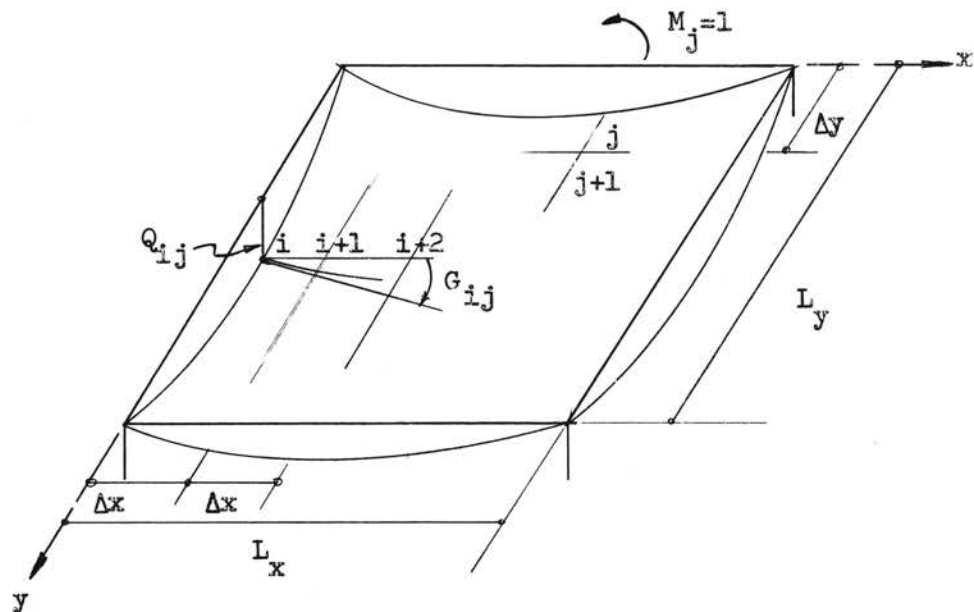


Figure 4.3. Angular and Angular-Displacement Carry-Overs

The moment can be replaced by a couple with forces  $\frac{1}{\Delta y}$  at  $j$  and  $j+1$ . From the definition,

$$G_{ij} = \frac{w_{i+1} - w_i}{\Delta x} = \frac{\Delta x \Delta y}{D} \frac{1}{\Delta x} \frac{1}{\Delta y} \left\{ \left( \eta_{(i+1)(j+1)} - \eta_{(i+1)j} \right) - \left( \eta_{i(j+1)} - \eta_{ij} \right) \right\}.$$

But,

$$\eta_{(i+1)j} = \eta_{i(j+1)}.$$

Substituting in the above equation,

$$G_{ij} = \frac{1}{D} \left\{ \eta_{(i+1)(j+1)} - 2\eta_{i(j+1)} + \eta_{ij} \right\}. \quad (4.11)$$

Similarly from the definition,

$$Q_{ij} = \frac{\Delta x}{D} \left( \eta_{i(j+1)} - \eta_{ij} \right). \quad (4.12)$$

If  $i$  is on edge parallel to  $x$ -axis and  $j$  on edge parallel to  $y$ -axis,

$$Q_{ij} = \frac{\Delta y}{D} \left( \eta_{i(j+1)} - \eta_{ij} \right). \quad (4.13)$$

If  $i$  and  $j$  are on parallel edges, (normal to  $x$ -direction)

$$G_{ij} = \frac{1}{D} \frac{\Delta x}{\Delta y} \left\{ \eta_{(i+1)(j+1)} - 2\eta_{i(j+1)} + \eta_{ij} \right\} \quad (4.14)$$

(normal to  $y$ -direction)

$$G_{ij} = \frac{1}{D} \frac{\Delta y}{\Delta x} \left\{ \eta_{(i+1)(j+1)} - 2\eta_{i(j+1)} + \eta_{ij} \right\} \quad (4.15)$$

4.4. Displacement Flexibility and Carry-Over. Consider a column supported rectangular plate to be acted upon by a unit shear at  $i$ . By definition, the displacement at  $i$  due to a unit shear at  $i$  is the displacement flexibility  $D_i$  (Figure 4.4).

$$D_i = w_i = \frac{\Delta x \Delta y}{D} \eta_{ii} \quad (4.16)$$

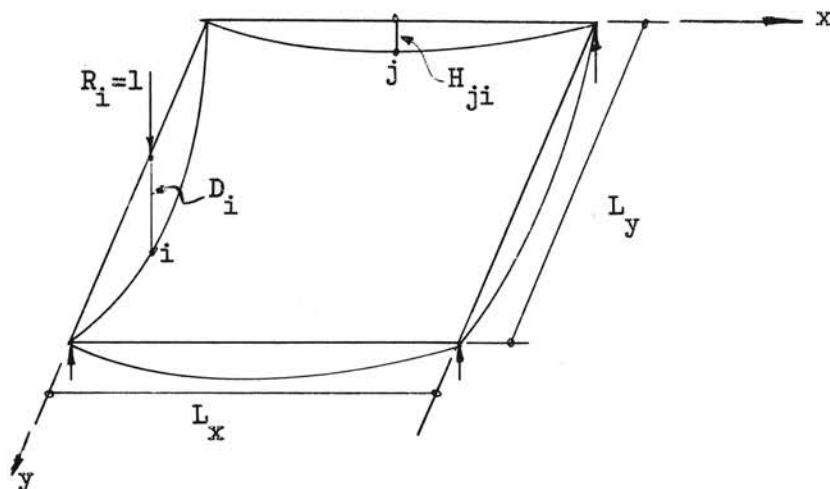


Figure 4.4. Displacement Flexibility and Carry-over

The displacement at  $j$  due to a unit shear at  $i$  is the displacement carry-over  $H_{ji}$ .

$$H_{ji} = w_j = \frac{\Delta x \Delta y}{D} \eta_{ji}$$

By virtue of the Maxwell-Betti Reciprocal Theorem  $H_{ji} = H_{ij}$ , the displacement at  $i$  due to a unit load at  $j$ . Therefore, it follows that

$$H_{ij} = \frac{\Delta x \Delta y}{D} \eta_{ij} = \frac{\Delta x \Delta y}{D} \eta_{ij} \quad (4.17)$$

#### 4.5. Beam Flexibilities.

(a) Angular and displacement load functions:

Consider a simply supported beam to be acted upon by its own weight (Figure 4.5). By definition, the slope of the beam at  $m$  and displacement at  $i$  are angular and displacement load functions  $\tau_m^B$  and  $\delta_i^B$  respectively.



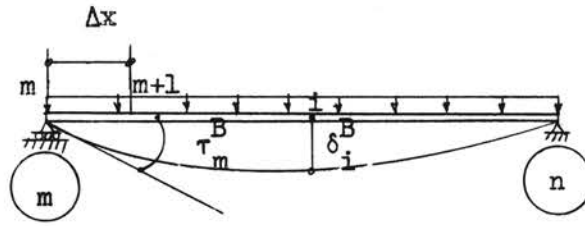


Figure 4.5. Angular and Displacement Load Functions of Beam

If  $\eta_{ij}^B$  is the influence coefficient for the deflection at  $i$  due to a unit load at  $j$ , then

$$w_{ij} = \frac{\Delta x^3}{EI} \eta_{ij}^B$$

where

$EI$  is the flexural rigidity of the beam.

The angular load function can now be expressed as

$$\tau_m^B = \frac{w_{m+1}}{\Delta x} = \frac{\Delta x^3}{EI} q \sum_{j=1}^p \eta_{(m+1)j}^B \quad (4.18)$$

where

$p$  is the number of strips in the beam and  $q$  is the weight of each strip.

The displacement load function becomes

$$\delta_i^B = \frac{\Delta x^3}{EI} q \sum_{j=1}^p \eta_{ij}^B \quad (4.19)$$

- (b) Displacement flexibility and displacement and displacement-angular carry-over:

Consider a simply supported beam  $mn$  to be acted upon by a unit shear at  $i$  (Figure 4.6). By definition the displacements at  $i$  and  $j$  due to unit shear at  $i$  are displacement flexibility  $D_i^B$  and displacement carry-over  $H_{ji}^B$  respectively.

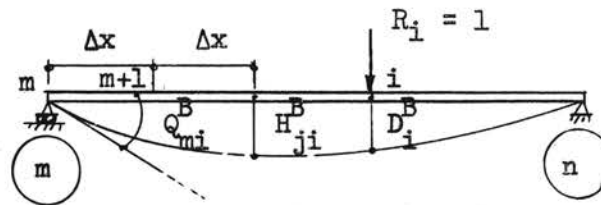


Figure 4.6. Displacement Flexibility and Carry-Overs of Beam

These can be expressed as

$$D_i^B = w_{ii} = \frac{\Delta x^3}{EI} \eta_{ii}^B \quad (4.20)$$

and

$$H_{ji}^B = w_{ji} = \frac{\Delta x^3}{EI} \eta_{ji}^B \quad (4.21)$$

The rotation at  $m$  due to unit shear at  $i$  is displacement-angular carry-over  $Q_{mi}^B$ .

$$Q_{mi}^B = \frac{w_{m+1}}{\Delta x} = \frac{\Delta x^2}{EI} \eta_{(m+1)i}^B \quad (4.22)$$

- (c) Angular flexibilities and angular and angular-displacement carry-overs:

Consider a simply supported beam  $mn$  to be acted upon by a unit moment at  $m$  (Figure 4.7). The slope at  $m$  due to a unit moment at  $m$  is the angular flexibility of the beam  $F_{mm}^B$ .

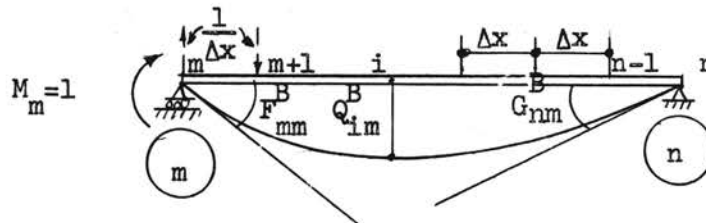


Figure 4.7. Angular Flexibilities and Carry-Over Functions of Beam

Replacing the unit moment by a statically equivalent couple of forces  $\frac{1}{\Delta x}$  a distance  $\Delta x$  apart as shown in Figure 4.6,

$$F_{mm}^B = \frac{w(m+1)(m+1)}{\Delta x} = \frac{\Delta x^3}{\Delta x} \frac{1}{EI} \eta_{(m+1)(m+1)}^B$$

or

$$F_{mm}^B = \frac{\Delta x^2}{EI} \eta_{(m+1)(m+1)}^B \quad (4.23)$$

The slope at  $n$  due to a unit moment at  $m$  is the angular carry-over  $G_{nm}^B$  (Figure 4.7),

$$G_{nm}^B = \frac{w(n-1)(m+1)}{\Delta x} = \frac{\Delta x^3}{\Delta x} \frac{1}{EI} \eta_{(n-1)(m+1)}^B$$

or

$$G_{nm}^B = \frac{\Delta x^2}{EI} \eta_{(n-1)(m+1)}^B \quad (4.24)$$

In view of the reciprocal relations for angular carry-overs and deflection influence coefficients, it can be written

$$G_{nm}^B = \frac{\Delta x^2}{EI} \eta_{(m+1)(n-1)} \quad (4.25)$$

The deflection at any point  $i$  on the beam due to a unit moment at  $m$  is the angular displacement carry-over  $Q_{im}^B$ .

$$Q_{im}^B = w_{i(m+1)} = \frac{\Delta x^3}{EI} \eta_{i(m+1)}^B \quad (4.26)$$

## CHAPTER V

### NUMERICAL EXAMPLE

The plate structure shown in Figure 5.1 is analyzed for a uniformly distributed load of 100 pounds per square foot. All the panels are four inches thick. Edge beams are provided around the plate structure. The dimensions of edge beams are:

width = 9 inches

Depth = 1 foot 6 inches.

Poisson's ratio is taken as zero. The structure is supported by rigid columns.

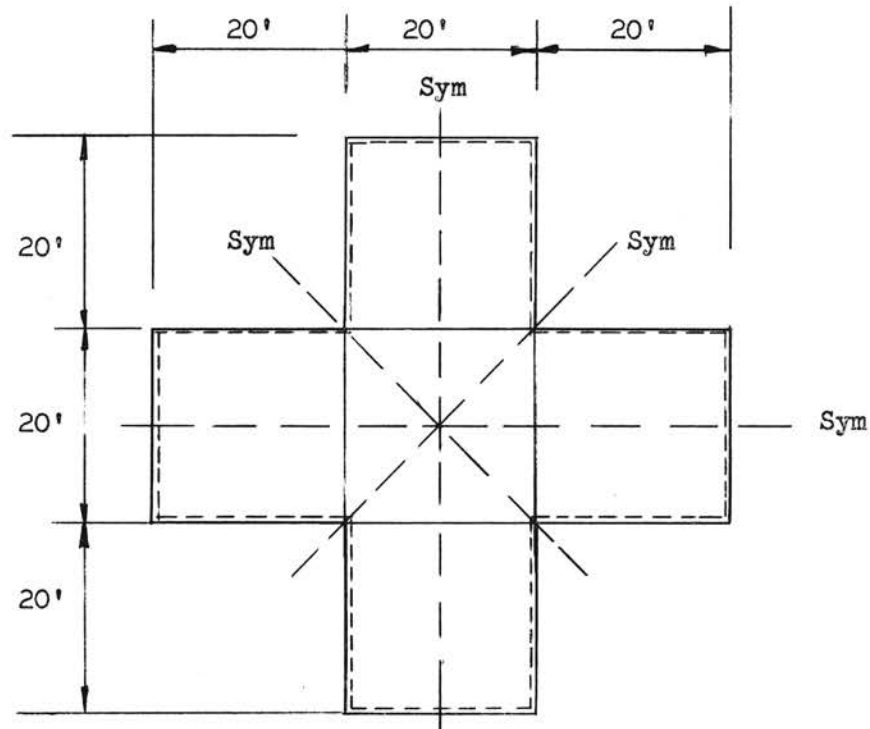


Figure 5.1. Continuous Plate Structure

A square panel supported by four columns at the corners is taken as a basic unit and is covered by a sixty-four unit finite difference network as shown in Figure 5.2.

	1	2	3	4	5	6	7	
8	9	10	11	12	13	14	15	16
17	18	19	20	21	22	23	24	25
26	27	28	29	30	31	32	33	34
35	36	37	38	39	40	41	42	43
44	45	46	47	48	49	50	51	52
53	54	55	56	57	58	59	60	61
62	63	64	65	66	67	68	69	70
	71	72	73	74	75	76	77	

Figure 5.2. Basic Panel

Deflection influence coefficients, obtained by taking advantage of symmetry of the basic unit as outlined in Chapter II, are presented in Table 5.1.















Deflection influence coefficients for a simply supported beam are calculated and presented in Table 5.2.

Table 5.2

$\eta_{ij}$ Deflection Influence Coefficients for Beam							
$i \backslash j$	1	2	3	4	5	6	7
1	2.1869	3.4997	4.0625	3.9900	3.4375	2.500	1.3128
2	3.4997	6.2500	7.4990	7.500	6.4900	4.7470	2.4990
3	4.0625	7.4990	9.6950	9.9940	8.8900	6.4980	3.4364
4	3.9900	7.500	9.9940	11.00	9.9940	7.5000	3.9900
5	3.4375	6.4980	8.8900	9.9940	9.6950	7.4990	4.0625
6	2.500	4.7470	6.4980	7.5000	7.4990	6.2500	3.4997
7	1.3128	2.4990	3.4375	3.9900	4.0625	3.4977	2.1869

The unknowns in the example are moments at points 12, 13, 14, 15 and 16, and reactions at points 1 to 11 (Figure 5.3).

All the angular and displacement functions are obtained by using the relations derived in Chapter IV and utilizing the deflection influence coefficients given in Tables 5.1 and 5.2. A matrix is formulated for the solution of unknowns and is presented on page 47.

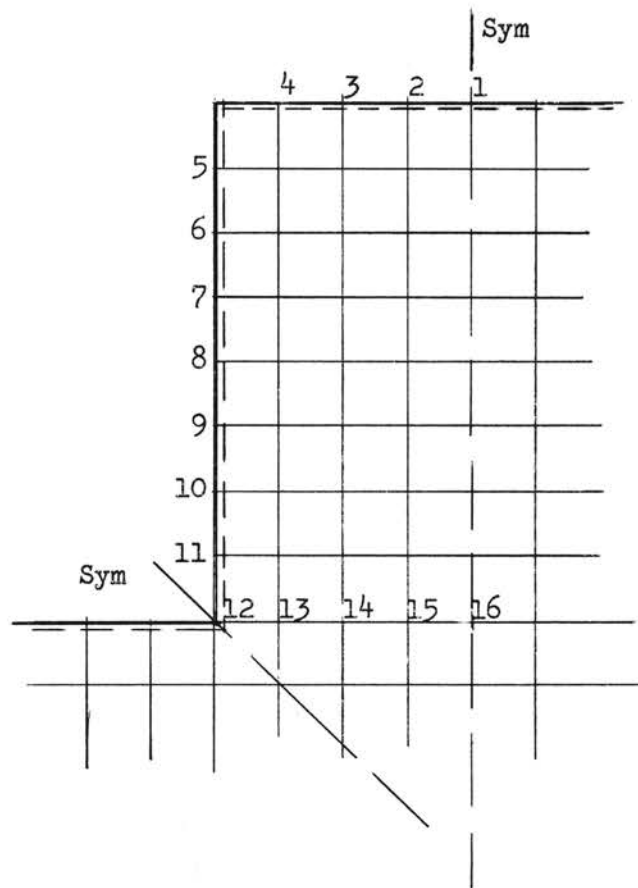


Figure 5.3. Reduced Plate Structure Due to Symmetry

1.803695	.790928	.751447	.634037	.300382	2.281720	3.198602	3.41022	3.24020	2.705230	1.94625	1.034221	.722121	.545236	.763123	.377028	M <sub>12</sub>	108.8334
.796928	1.66254	.85947	.733182	.346977	1.42736	1.18902	1.12250	1.095089	.956108	.733020	.499021	.341262	.55023	.776250	.416205	M <sub>13</sub>	83.2576
.751447	.85947	1.62008	.885564	.41506	1.07812	1.88312	1.75812	1.53821	1.29712	.898290	.848260	.439272	.60421	.853123	.462091	M <sub>14</sub>	71.1907
.634037	.733182	.885564	1.588068	.516741	.981002	1.7351	2.11210	1.86223	1.58682	1.33002	1.18202	.59202	.781209	.915206	.492062	M <sub>15</sub>	61.8972
.600764	.693954	.830812	1.033482	1.167931	.92012	1.636078	2.02093	2.1023	1.7052	1.44023	1.2700	.616200	.825062	.962036	.505267	M <sub>16</sub>	58.6670
2.281720	1.42736	1.07812	.981002	.46006	6.202275	8.74232	9.46421	8.88562	7.54011	5.43112	2.841192	.78629	1.42902	1.92518	1.29001	-R <sub>11</sub>	129.5030
3.198602	1.18902	1.88312	1.73510	.818039	8.74232	15.63753	17.6198	22.3501	14.3570	10.37282	5.43127	1.37122	2.62088	3.41202	2.15002	-R <sub>10</sub>	230.07029
3.41022	1.12250	1.75812	2.1121	1.01046	9.46421	17.6198	23.0452	22.9801	19.75292	14.47022	7.49282	1.76208	3.24902	4.3307	2.59697	-R <sub>9</sub>	300.2082
3.24020	1.095089	1.53821	1.86223	1.0511	8.885623	22.3501	22.9801	25.8329	22.98012	17.3643	8.920170	2.2187	3.89602	4.99672	2.62081	-R <sub>8</sub>	322.0072
2.70523	.956108	1.29712	1.58682	.8526	7.54011	14.3570	19.75292	22.98012	23.0452	17.6209	9.46421	2.24542	3.8972	4.8572	2.59002	-R <sub>7</sub>	300.2082
1.94625	.733020	.898290	1.33002	.72011	5.43112	10.37282	14.47022	17.3643	17.6209	15.63722	7.95022	1.95452	3.3372	4.0628	2.13628	-R <sub>6</sub>	230.07029
1.034221	.499021	.84826	1.18202	.6350	2.8411920	5.43127	7.49282	8.92017	9.46421	7.95022	6.20275	1.24290	2.0072	2.41985	1.27622	-R <sub>5</sub>	129.5030
.722121	.341262	.439272	.59202	.30810	.786289	1.37122	1.76208	2.2189	2.24542	1.95452	1.2429	5.60277	12.1078	13.49202	7.4925	-R <sub>4</sub>	129.5030
.545236	.550230	.60421	.781209	.41253	1.42902	2.62088	3.24902	3.89602	3.8972	3.3372	2.0072	12.1078	13.6402	25.4602	14.6129	-R <sub>3</sub>	230.07029
.763123	.776250	.853123	.915206	.481016	1.92519	3.41202	4.3307	4.99672	4.8572	4.06282	2.41985	13.49202	25.4602	27.9952	19.4026	-R <sub>2</sub>	300.2082
.377028	.416205	.462091	.492062	.25263	1.29001	2.15002	2.59697	2.62081	2.59002	2.13628	1.27622	7.4925	14.6129	19.402	19.5322	-R <sub>1</sub>	322.0072

The solution of this matrix yields the final results which are:

$$M_{12} = - 58.3272 \text{ kip ft.}$$

$$M_{13} = - 41.6920 \text{ kip ft.}$$

$$M_{14} = - 5.5107 \text{ kip ft.}$$

$$M_{15} = + 10.4092 \text{ kip ft.}$$

$$M_{16} = + 3.7120 \text{ kip ft.}$$

$$R_1 = + 1.7717 \text{ kips}$$

$$R_2 = + 1.0526 \text{ kips}$$

$$R_3 = + 0.8602 \text{ kips}$$

$$R_4 = + 0.6072 \text{ kips}$$

$$R_5 = + 0.7824 \text{ kips}$$

$$R_6 = + 0.9526 \text{ kips}$$

$$R_7 = + 1.0269 \text{ kips}$$

$$R_8 = + 1.0401 \text{ kips}$$

$$R_9 = + 1.5652 \text{ kips}$$

$$R_{10} = - .9652 \text{ kips}$$

$$R_{11} = - 3.5941 \text{ kips}$$



## CHAPTER VI

### SUMMARY AND CONCLUSIONS

6.1. Summary. The application of flexibility methods to two-way continuous rectangular plates supported by flexible beams is presented. The continuous structure is isolated into appropriate basic structures and the support moments and edge shears are selected as redundants. A method of obtaining deflection influence coefficients for the basic structure by a finite difference approximation is given. Angular, displacement and load functions of the basic structure are introduced and are expressed in terms of the deflection influence coefficients. Deformation equations in terms of these functions and the redundants are obtained utilizing the conditions of compatibility of deformations over a continuous support and between plate and the supporting beam. The theory is illustrated by a numerical example.

6.2. Findings and Conclusions. The flexibility method of approach to two-way continuous rectangular plates is direct, can be used for any type of loading, and affords significant reduction in the number of unknowns. The type of basic structure chosen makes possible the application of the flexibility method to a wide range of problems.

The availability of deflection influence coefficient tables for various length-width ratios of the basic structure is a prerequisite to this method. Evaluation of such tables can be accomplished readily by the procedure indicated in this study, with a sufficiently high degree of accuracy obtainable, in most cases, using the same size network.

## BIBLIOGRAPHY

- (1) Marcus, H. Die Theorie Elastischer Gewebe und ihre Anwendung auf die Berechnung biegsamer Platten. Berlin: Julius Springer, 1932.
- (2) Jensen, V. P. "Solutions for Certain Rectangular Slabs Continuous Over Flexible Supports." University of Illinois Engineering Experiment Station Bulletin 303, June 3, 1938.
- (3) Hawk, R. D. "The Analysis of Continuous Rectangular Plates by Carry-Over Moments." (unpub. thesis, Oklahoma State University), 1961.
- (4) Newmark, N. M. "A Distribution Procedure for the Analysis of Slabs Continuous over Flexible Beams." University of Illinois Engineering Experiment Station Bulletin 304, June, 1938.
- (5) Southerland, J. G., Goodman, L. E., and Newmark, N. M. "Analysis of Plates Continuous over Flexible Beams." University of Illinois Civil Engineering Studies, Structural Research Series No. 42, January, 1953.
- (6) Nielson, N. J. Bestemmelse af Spaendinger i Plader ved Anvendelse af Differensligninger. Copenhagen: 1920.
- (7) Bittner, E. Momententafeln und Einflussfächen für Kreuzweise bewehrte Eisenbetonplatten. Vienna: Julius Springer, 1938.
- (8) Maugh, L. C., and Pan, C.W. "Moments in Continuous Rectangular Slabs on Rigid Supports." Transactions, ASCE, Vol. 107, 1942, p. 1118.
- (9) Engelbreth, K. En Methode for Tilnaermet Beregning au Kontinuerlige Toveisplater. Betong, Vol. 30, No. 2, 1945, pp. 99-115.
- (10) Seiss, C. P., and Newmark, N. M. "Moments in Two-way Concrete Floor Slabs." University of Illinois Engineering Experiment Station Bulletin 385, February, 1950.
- (11) Lechter, Hanson. "Analysis of Continuous Rectangular Plates on Rigid Supports by Flexibility Methods." (unpub. M.S. thesis, Oklahoma State University), 1962.
- (12) Tuma, J. J., Havner, K.S. and French, S.E. "Analysis of Flat Plates by the Algebraic Carry-Over Method, Vol. II, Tables." School of Civil Engineering Research Publication, Oklahoma State University, No. 2, 1958.

- (13) Ang, A. H. S., and Newmark, N. M. "A Numerical Procedure for the Analysis of Continuous Plates." 2nd Conference on Electronic Computation, ASCE, 1960, pp. 379-413.
- (14) Tuma, J. J. "Analysis of Continuous Beams by Carry-Over Moments." Proceedings, ASCE, Vol. 84, 1958.

VITA

Vatti Arla Reddy

Candidate for the Degree of

Master of Science

Thesis: ANALYSIS OF CONTINUOUS RECTANGULAR PLATES ON FLEXIBLE BEAM  
SUPPORTS BY FLEXIBILITY METHODS

Major Field: Civil Engineering

Biographical:

Personal Data: Born October 19, 1935 in Patibanda, India, the son  
of Shouri Reddy and Thecklamma.

Education: Graduated from St. Paul's High School, Phirangipuram,  
India in June, 1952. Joined Andhra Christian College, Guntur,  
India and passed the Intermediate Arts and Science examination,  
May, 1954. Joined Government Engineering College, Anantapur,  
India, July, 1954. Completed the requirements and received  
the degree of Bachelor of Engineering from Sri Venkateswara  
University, Tirupathi, India in June, 1958. Completed the  
requirements for the Master of Science degree in May, 1963,  
at Oklahoma State University.

Experience: Worked as Research Assistant from August, 1958 to June,  
1961 in Ports and Harbours division at Central Water and Power  
Research Station, Poona, India.