

FINITE ELEMENT ANALYSIS



# Predictive Engineering

## LS-DYNA<sup>®</sup> Handbook

Analysis Theory and Techniques for Structural Mechanics

An overview of the core analysis features used by LS-DYNA<sup>®</sup> to simulate highly nonlinear static (implicit) and dynamic (implicit/explicit) behavior in engineered structures and systems.



LST



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## COURSE OUTLINE

1.	INTRODUCTION .....	11
1.1	WHAT THE STUDENT CAN EXPECT .....	11
1.2	WHAT WE COVER .....	11
1.3	HOW WE DO IT .....	11
1.4	HOW TO BE SUCCESSFUL WITH AS A LS-DYNA SIMULATION ENGINEER (TOP-OF-THE-PACK) .....	11
1.5	GENERAL APPLICATIONS .....	12
1.6	SPECIFIC APPLICATIONS (COURTESY OF PREDICTIVE ENGINEERING) .....	13
2.	WHAT IS LS-DYNA? .....	25
2.1	HOW WE VISUALIZE THE LS-DYNA ANALYSIS PROCESS .....	25
3.	IMPLICIT VERSUS EXPLICIT ANALYSIS .....	26
3.1	WHAT WE ARE SOLVING .....	26
3.2	EXPLICIT (DYNAMIC) – ONE MUST HAVE “MASS” TO MAKE IT GO .....	27
3.3	IMPLICIT (DYNAMIC OR STATIC) .....	27
3.3.1	Pros and Cons of Explicit v Implicit .....	28
4.	LS-DYNA GETTING STARTED WITH THE FUNDAMENTALS .....	29
4.1	LS-DYNA KEYWORD MANUAL .....	29
4.2	KEYWORD SYNTAX .....	29
4.3	UNITS .....	30
4.4	REFERENCE MATERIALS AND PROGRAM DOWNLOAD .....	31
4.5	SUBMITTING LS-DYNA ANALYSIS JOBS WITH LS-RUN .....	31
4.5.1	Internal LST FAQ - <a href="https://ftp.lstc.com/anonymous/outgoing/support/FAQ/">https://ftp.lstc.com/anonymous/outgoing/support/FAQ/</a> .....	32
4.6	LS-DYNA OUTPUT FILES (RESULTS AND MESSAGE FILES) AND DATABASE REQUESTS AND MANAGEMENT .....	34
4.7	WORKSHOP: 1A - LS-DYNA GETTING STARTED – COMMON KEYWORD DECK FORMAT ERRORS .....	35
4.8	WORKSHOP 1B – LS-DYNA GETTING STARTED .....	36
5.	FUNDAMENTAL MECHANICS OF EXPLICIT ANALYSIS .....	37
5.1	EXPLICIT NUMERICAL FLOWCHART .....	37
5.2	TIME STEP SIGNIFICANCE (COURANT-FRIEDRICHS-LEWY (CFL) CHARACTERISTIC LENGTH) .....	38
5.2.1	Is the CFL based on Elements or Nodes? .....	39
5.2.2	As the Mesh Size Changes, So Does the Explicit Time Step .....	40
5.3	MASS SCALING: (EVERYBODY DOES IT BUT NOBODY REALLY LIKES IT) – CHANGING THE WAVE SPEED .....	41
5.3.1	Instructor Led Workshop: 1 – Mass Scaling .....	41

5.3.2	Workshop: 2 - LS-DYNA Mass Scaling Basics .....	42
5.3.3	Instructor Led Workshop: 2 - Mass Scaling Advanced .....	44
5.4	IMPLICIT MESH VERSUS EXPLICIT MESH CHARACTERISTICS .....	46
5.4.1	Instructor Led Workshop: 3 - Implicit versus Explicit Mesh Differences.....	46
5.4.2	A Short Discussion on Element Quality (aka Jacobian) .....	47
5.4.2.1	An Example of the Assembly of Equations for Static Stress Analysis .....	48
5.4.2.2	Gaussian Integration for Isoparametric Elements .....	50
5.4.2.3	How Can One Leverage Element Quality to Create Higher Quality Analyses?.....	51
5.5	SUMMARY OF EXPLICIT TIME INTEGRATION .....	52
6.	EXPLICIT ELEMENT TECHNOLOGY.....	53
6.1	ELEMENT TYPES IN LS-DYNA.....	53
6.2	ONE GAUSSIAN POINT ISOPARAMETRIC SHELL ELEMENTS AND HOURGLASSING .....	54
6.2.1	Instructor Led Workshop: 4 - Explicit Element Technology   A: Side Bending .....	54
6.2.2	Instructor Led Workshop: 4 - Explicit Element Technology   B: Out-of-Plane Bending with Plasticity .....	55
6.2.3	Workshop: 3 - Building the Better Beam.....	56
6.2.4	Workshop: 4 - Hourglass Control/Hourglass .....	58
6.3	WORKSHOP: 5 – SOLID ELEMENT TECHNOLOGY – HEX AND TET FORMULATIONS .....	59
6.3.1	Workshop 5 – Solid Element Technology – Hourglass Control .....	60
6.4	SCALAR ELEMENTS (E.G., NASTRAN CBUSH) OR LS-DYNA “DISCRETE BEAM” .....	61
6.4.1	Workshop 6 - Discrete Beam (Spring Away).....	65
7.	LS-PREPOST.....	67
7.1	WORKSHOP: 7 - LS-PREPOST   WORKSHOP 6 (PARTIAL EXECUTION).....	67
8.	MATERIAL MODELING .....	68
8.1	BASIC REVIEW OF MATERIAL MODELS AVAILABLE IN LS-DYNA .....	68
8.1.1	So Many Material Models and So Many Questions .....	68
8.2	LS-DYNA KEYWORD USER’S MANUAL: VOLUME II – MATERIAL MODELS.....	69
8.3	PART I: METALS.....	70
8.3.1	Engineering Stress-Strain vs True Stress-Strain.....	70
8.3.2	Material Failure and Experimental Correlation.....	71
8.4	WORKSHOP: 8 - ELASTIC-PLASTIC MATERIAL MODELING (*MAT_024).....	72
8.5	MATERIAL MODELING OF STAINLESS STEEL - *MAT_024 (CURVE) OR *MAT_098 (EQUATION) .....	74
8.6	STRAIN RATE SENSITIVITY OF METALS.....	75
8.7	PART II: PLASTICS, ELASTOMERS AND FOAMS .....	76

8.7.1	Modeling Plastics, Elastomers vs Foams (Viscoelasticity).....	76
8.8	MATERIAL MODELS FOR MODELING FOAMS.....	77
8.9	MODELING TECHNIQUES FOR ELASTOMERS AND FOAMS.....	78
8.9.1	Workshop: 9 - Modeling an Elastomer (*MAT_181) Ball with Hex and Tet Elements.....	79
8.10	PART III: COMPOSITE OR LAMINATE MATERIAL MODELING.....	80
8.10.1	Workshop: 10 - Composite Materials - Basic Understanding Using *MAT_054.....	81
8.10.1.1	Misc Important Notes on Composites .....	83
8.11	PART IV: EQUATION OF STATE (EOS) MATERIAL MODELING.....	84
8.11.1	Modeling Water with *EOS_GRUNEISEN and *MAT_NULL.....	86
8.12	MATERIAL FAILURE SIMULATION .....	87
8.12.1	Basic Methods of Modeling Failure: Material versus Bond Failure .....	87
8.13	WORKSHOP: 11 - MODELING GENERAL MATERIAL FAILURE.....	88
8.14	MODELING RIGID BODIES.....	89
8.14.1	Rigid Materials (*MAT_020 or *MAT_RIGID).....	89
8.14.2	Workshop: 12 - Using Rigid Bodies.....	90
8.14.2.1	Instructor Led Workshop: 5 – Connections From RBE2 /CNRB and RBE3/ CI.....	91
8.15	VERIFICATION OF MATERIAL MODEL .....	92
9.	CONTACT .....	93
9.1	DEFINITION OF CONTACT TYPES.....	93
9.1.1	What is Implicit with the _AUTOMATIC Option? .....	93
9.1.1.1	Efficient Contact Modeling.....	93
9.2	GENERAL CONTACT TYPES .....	94
9.2.1	In *CONTACT, What Does _SURFACE Mean?.....	94
9.2.2	Additional Options: Optional Card A - soft=2 and depth=5 “The Default” .....	95
9.2.2.1	Instructor Led Workshop: 6A – Basics of Contact .....	95
9.2.2.2	Instructor Led Workshop 6A – Basics of Contact – A Little Detail That Could Whack You.....	96
9.2.3	Contact when things ERODE.....	97
9.2.4	MORTAR Contact.....	98
9.2.4.1	_MORTAR _ERODING {Built-In} .....	98
9.3	CONTACT ENERGY.....	100
9.3.1	A Brief Comment on Energy Reports .....	100
9.4	WORKSHOP: 13 - UNDERSTANDING BASIC CONTACT MECHANICS.....	101
9.4.1.1	Student Notes for Workshop – Understanding Basic Contact Mechanics.....	104

9.4.1.2	Addendum to Workshop: Contouring Contact Pressures.....	105
9.5	WORKSHOP: 14 - BEAM-TO-BEAM CONTACT.....	106
9.6	MISCELLANEOUS COMMENTS ON CONTACT.....	107
9.6.1	Contact Numerical Efficiency or Why Not All _MORTAR All the Time? .....	107
9.6.2	Why Paying Attention to the Contact time Step is Important .....	108
9.6.3	Instructor Led Workshop: 7A – Sliding Interface Energy – Not Always About “Rules-of-Thumb” .....	110
9.7	CONTACT BEST PRACTICES.....	111
9.8	MESH TRANSITIONS: TIED CONTACT FOR EFFICIENT IDEALIZATION, CONNECTIONS, WELDING, MESH TRANSITIONS AND ETC.....	112
9.8.1	_TIED Contact or Gluing .....	112
9.8.1.1	Summary and Recommendations of _TIED Usage .....	112
9.8.1.2	Some Important _TIED Concepts to Think About .....	113
9.8.1.3	What About All Those Other _TIED Formulations?.....	114
9.8.1.4	For Those Believers in the KISS Method of _TIED Contact .....	114
9.8.2	Workshop: 15A - Tied Contact for Solids (3 dof) _TIED_NODES_TO_SURFACE_CONSTRAINED_OFFSET .....	115
9.8.3	Workshop: 15B - Tied Contact for Shells (6 DOF) _TIED_SHELL_EDGE_SURFACE_CONSTRAINED_OFFSET.....	116
9.8.4	Instructor Led Workshop: 7B - _TIED Bad Energy (or why we use _BEAM_OFFSET).....	117
9.8.5	Workshop 16: <i>Surfb</i> Class in _TIED Connections (Student Bonus).....	119
10.	CONNECTIONS VIA JOINTS .....	121
10.1	JOINTS OR *CONSTRAINED_JOINT_ .....	121
10.2	HOW JOINTS WORK .....	122
10.3	WORKSHOP: 17A – SPHERICAL JOINT BETWEEN A SHELL AND SOLID .....	123
10.4	WORKSHOP: 17B - CYLINDRICAL JOINT BETWEEN TWO NESTED CYLINDERS .....	124
10.4.1	Who Uses Joints?.....	125
11.	DAMPING.....	126
11.1	GENERAL, MASS AND STIFFNESS DAMPING .....	126
11.1.1	*DAMPING_option .....	126
11.1.2	*DAMPING_FREQUENCY_RANGE_DEFORM .....	126
11.1.3	Material Damping (e.g., elastomers and foams).....	127
11.1.4	General Example on Material Damping .....	127
11.2	INSTRUCTOR LED WORKSHOP: 8 – DAMPING OF TRANSIENT VIBRATING STRUCTURES.....	129
12.	LOADS, CONSTRAINTS AND RIGID WALLS .....	130
12.1	LOADS.....	130
12.1.1	Initialization Loads (*INITIAL_).....	130

12.1.2	Point and Pressure Loads (*LOAD_NODE_ & _SEGMENT).....	130
12.1.3	Body Loads (*LOAD_BODY_ ).....	130
12.1.4	Rigid Walls (e.g., *RIGIDWALL_MOTION).....	130
12.1.5	Boundary (e.g., *BOUNDARY_PRESCRIBED_ ).....	130
12.1.5.1	Prescribed Nonlinear or Curvilinear Motion of Node, Node Sets or Rigid Bodies.....	130
12.1.5.2	Load Example: Fixed Cylindrical Displacement via Clever Use of Rigid Body and *CONSTRAINED_EXTRA_NODES_SET.....	132
12.2	WORKSHOP: 18 - DROP TEST OF PRESSURE VESSEL.....	133
13.	DATA MANAGEMENT AND STRESS AVERAGING .....	136
13.1.1	Stress Reporting and Stress Averaging in LS-DYNA/LSPF.....	137
	Instructor Led Workshop: 9 - Stress Reporting and Stress Averaging   Shells.....	137
14.	LOAD INITIALIZATION BY DYNAMIC RELAXATION AND IMPLICIT ANALYSIS .....	138
14.1	INITIALIZATION OF GRAVITY, BOLT PRELOAD AND OTHER INITIAL STATE CONDITIONS.....	138
14.1.1	Stress Initialization .....	138
14.1.2	Dynamic Relaxation (DR) *CONTROL_DYNAMIC_RELAXATION.....	138
14.1.3	Initializing Displacements and/or Stress with *INTERFACE_SPRINGBACK_LSDYNA.....	139
14.2	WORKSHOP: 19 - DYNAMIC RELAXATION - BOLT PRELOAD PRIOR TO TRANSIENT .....	140
15.	IMPLICIT-EXPLICIT SWITCHING FOR BURST CONTAINMENT.....	141
15.1	HIGH-SPEED ROTATING EQUIPMENT – *CONTROL_ACCURACY .....	141
15.1.1	Workshop: 20 - Implicit-Explicit Switching for Turbine Spin Up.....	142
16.	SMOOTHED PARTICLE HYDRODYNAMICS (SPH) {MESH FREE METHOD}.....	143
16.1	INTRODUCTION.....	143
16.1.1	A Little Bit of Theory (skip this if you don't like math...) .....	143
16.1.2	Lagrangian vs Eulerian.....	145
16.1.3	Types of Simulations with SPH .....	146
16.1.4	Common Keywords for SPH .....	146
16.2	WORKSHOP: 21A - SPH GETTING STARTED – BALL HITTING SURFACE.....	147
16.3	WORKSHOP: 21B - SPH GETTING STARTED - FLUID MODELING .....	148
16.4	WORKSHOP: 21C – SPH GETTING STARTED – BIRD STRIKE .....	149
16.4.1	Bird Strike Models.....	150
16.5	REFERENCES.....	151
17.	EXPLICIT EXAMINATION.....	152
18.	EXPLICIT MODEL CHECK-OUT AND RECOMMENDATIONS .....	154
18.1	UNITS .....	154

18.2	MESH .....	154
18.2.1	Using Surface Elements to Improve Stress Reporting Accuracy .....	154
18.3	MASS SCALING .....	154
18.4	D3HSP FILE (LS-DYNA EQUIVALENT TO THE NASTRAN F06 FILE) .....	154
18.5	ENERGY PLOTS .....	155
18.5.1	Sliding Interface Energy (Contacts) .....	155
18.6	MATERIAL MODELING ERRORS.....	155
18.7	CONTACT OPTIONS WITH RECOMMENDATIONS AND *CONTROL_CONTACT OPTIONS.....	156
18.7.1	*CONTROL_TIED Global Recommendation.....	157
18.8	CONTROL CARDS WITH RECOMMENDATIONS.....	158
18.9	DATABASE CARDS WITH RECOMMENDATIONS.....	159
18.10	EXPLICIT ELEMENT RECOMMENDATIONS.....	159
18.11	ETC.....	159
19.	IMPLICIT ANALYSIS .....	160
19.1	INTRODUCTION.....	160
19.1.1	Why Implicit?.....	160
19.1.2	What we cover .....	160
19.1.3	What Sort of Problems Can We Solve in Implicit? .....	161
19.2	IMPLICIT VERSUS EXPLICIT ANALYSIS.....	167
19.2.1	What We Are Solving.....	167
19.2.2	Review of Mathematical Foundation of Nonlinear Dynamic Implicit Analysis .....	168
19.3	LINEAR ELASTIC IMPLICIT ANALYSIS (LS-DYNA DOUBLE-PRECISION SOLVER).....	169
19.3.1	Keywords Used in this Section for Isoparametric Shell and Solid Elements .....	169
19.4	SHELL ELEMENT TECHNOLOGY FOR LINEAR ELASTIC IMPLICIT ANALYSIS.....	170
19.4.1	In-Plane and out-of-Plane ( <i>nips</i> ) Shell Element Integration.....	170
19.4.1.1	Why Is This Important to a Simulation Engineer?.....	170
19.4.1.2	Workshop: 22A - Linear Elastic Analysis – Shells - Stress Concentrations .....	171
19.4.1.3	Workshop: 22B - Linear Elastic Analysis – Shells – Out-of-Plane Integration.....	172
19.5	SOLID ELEMENT TECHNOLOGY FOR LINEAR ELASTIC STRESS ANALYSIS.....	173
19.5.1.1	Keywords Used in this Section for Solid Elements.....	174
19.5.1.2	Workshop: 23 – Linear Elastic Analysis – Solids - Hex & Tets .....	175
19.6	BEAM ELEMENT TECHNOLOGY FOR LINEAR ELASTIC STRESS ANALYSIS.....	178
19.6.1	Beam Integration (QR) Setting: Rectangular .....	178



19.6.2	Contact with Beams.....	178
19.6.3	Beam Integration (Cylindrical Solid and Tube).....	179
19.6.4	Workshop: 24 - Linear Elastic Analysis – Beam Analysis .....	180
19.7	CHECKLIST FOR IMPLICIT STATIC, LINEAR ELASTIC ANALYSIS IN LS-DYNA .....	181
19.8	GEOMETRIC AND MATERIAL NONLINEARITY .....	182
19.8.1	Material Nonlinearity in Shells: Out-of-Plane Gaussian Integration is Important .....	182
19.8.2	For Limited Material Plasticity (<20%) Go Lobatto (see *CONTROL_SHELL, <i>intgrd</i> =1) – Finessing Implicit Stress Results .....	183
19.8.2.1	Classic Tradeoff: To Gauss or To Lobatto – that is the Question? .....	183
19.8.3	New Keyword Commands Used in this Section for Static Nonlinear Implicit Analysis .....	185
19.8.4	Workshop: 25 – Implicit Nonlinear Material Analysis.....	186
19.9	CONTACT.....	187
19.9.1	General Comment and Focus on Mortar Contact.....	187
19.9.2	General Mortar Contact Types.....	188
19.9.3	Workshop: 26A – Implicit Contact – Static Stress Analysis with Bolt Preload .....	189
19.9.3.1	Bolt Preload Discussion via Solid Elements .....	189
19.9.4	Workshop: 26B - Contact - Shrink Fit Analysis .....	190
19.9.5	Workshop: 26C – 4pt Bend Composite Bend Test .....	191
19.9.6	Tied Contact for Mesh Transitions, Welding and Gluing.....	192
19.9.7	Checklist for Implicit Nonlinear Contact Analysis in LS-DYNA.....	193
19.9.8	But My Boss Says That Using “Dynamics” is Wrong for a Static Solution? .....	194
19.10	RIGID BODY USAGE .....	195
19.10.1	RBE2 (Nastran) to CNRB .....	195
19.11	NONLINEAR TRANSIENT DYNAMIC ANALYSIS (IMPLICIT): INITIALIZATION TO TRANSIENT DYNAMIC.....	196
19.11.1	What is a Satisfactory Implicit Time Step for a Transient Event? .....	196
19.11.2	Workshop: 27 – Implicit - Nonlinear transient Dynamic Analysis.....	197
19.11.2.1	Part I: Normal Modes Analysis (Eigenvalue) with Load Application .....	197
19.11.2.2	Part II: Implicit Nonlinear Transient Dynamic Analysis .....	199
19.12	LINEAR DYNAMICS: IT IS ALL ABOUT THE NORMAL MODES .....	200
19.12.1	Normal Modes Analysis.....	201
19.12.1.1	Workshop: 28 - Normal Modes Analysis.....	202
19.12.2	Response Spectrum Analysis or Shock Response Analysis.....	203
19.12.2.1	Workshop: 29 - Response Spectrum Analysis of Bracket .....	204
19.12.3	PSD Analysis.....	205

19.12.3.1	Workshop: 30 - PSD Analysis and Zero-Crossing Frequencies .....	206
20.	IMPLICIT MULTI-PHYSICS: COUPLED THERMAL-STRESS ANALYSIS .....	208
20.1.1.1	Getting Started with Coupled Thermal-Stress Analysis.....	208
20.1.2	Workshop 31: Couple Thermal-Stress Analysis.....	209
20.2	IMPLICIT CHECK-OUT AND RECOMMENDATIONS .....	210
20.2.1	Model Construction Recommendations .....	210
20.2.2	Implicit Keyword Cards and Recommendations .....	211
20.2.3	Convergence Troubleshooting and Solution Speed Optimization .....	213
20.2.4	General Troubleshooting.....	213
20.2.5	Convergence – How to Find It .....	213
20.2.6	D3Iter Plot Database to Troubleshoot Abnormal Displacements .....	214
20.2.7	Don't Forget About the Implicit Time Step for Transient, Dynamic Analyses.....	214
20.2.8	Comments on LS-DYNA Output Messages and Their Significance.....	215
21.	TROUBLESHOOTING IMPLICIT ANALYSES.....	216
21.1	EXPLICIT ALWAYS RUNS WHILE IMPLICIT RARELY RUNS: WHY? .....	216
21.1.1	What is the Residual? .....	216
21.1.1.1	Workshop: The Basics of Convergence – Displacement Norm *  du/ u  .....	217
21.2	WHY IS IMPLICIT SUCH A BAD BOY?.....	218
21.3	IMPLICIT STABILITY DIAGNOSTICS.....	219
21.4	IMPLICIT RESIDUAL FORCE CONVERGENCE.....	220
21.4.1	But Can it Go Faster?.....	221
21.5	DEEP DIVE INTO MODEL CONVERGENCE .....	221
22.	DISCRETE ELEMENT METHOD.....	222
23.	FLUID STRUCTURE INTERACTION AND MULTI-PHYSICS IN LS-DYNA.....	223

## 1. INTRODUCTION

### 1.1 WHAT THE STUDENT CAN EXPECT

This class is directed toward the engineering professional simulating highly nonlinear, static and dynamic problems involving large deformations and contact between multiple bodies. What this means in layman terms, is that we will provide a realistic foundation toward the practical usage of LS-DYNA.

### 1.2 WHAT WE COVER

- Nonlinear Explicit and Implicit FEA Mechanics
- The technology of creating accurate nonlinear, static and transient FEA models
- How to do your own research to create more advanced simulations
- Our condensed experience and that of our colleague's to help you *not* repeat our mistakes

### 1.3 HOW WE DO IT

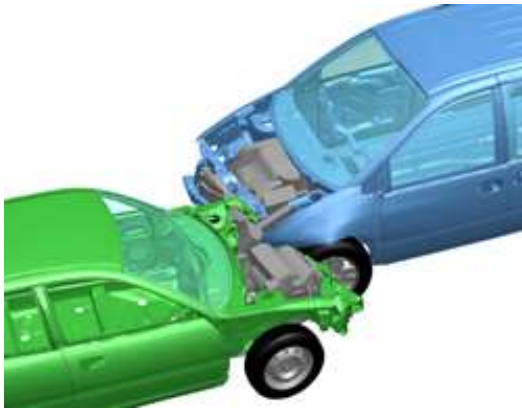
- The class covers the basics in a hands-on manner as taught by engineers that has had to live by what they have validated.
- Each day (four hour session) will have three to four Workshops. Each Workshop is part theory, part demonstration and part hands-on practice. Videos are provided for most Workshops thereby allowing the student to relax and follow along at their own pace. These videos cover the basics and also provide insight into the many tips and tricks that make LS-DYNA the world's most complete and accurate simulation code.
- A break is provided mid-way where students can pause, stretch and perhaps ask the instructor more detailed questions that might not be appropriate to involve the full class.
- Students are encouraged to turn off their email, text messaging and other forms of digital/social media during class time.

### 1.4 HOW TO BE SUCCESSFUL WITH AS A LS-DYNA SIMULATION ENGINEER (TOP-OF-THE-PACK)

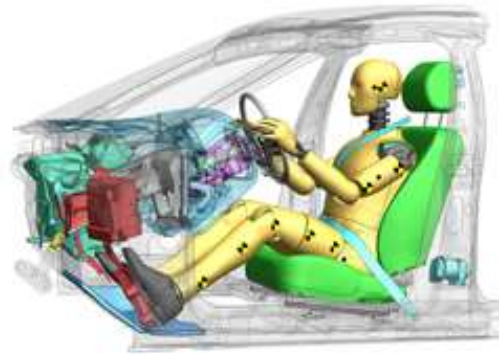
- You are already way ahead of the pack by simply attending this class. You have started on the journey of how to be more successful with LS-DYNA. It is this simple. To be successful, as far as we know, it requires:
  - Reading (very traditional but with LS-DYNA it is necessary to read the manual (RTM), read again and most likely for us normal people, read again;
  - Attend courses since it breaks up the learning process and opens doors to new avenues of learning and knowledge;
  - Be open to new ideas and then once again RTM and read some more;
  - After all this reading, one has to do some organic learning. That means building small models to explore options and mechanics and to suffer a bit prior to calling your colleagues for help;
  - Lastly, don't be hesitant to reach out for help once you have read, built small models to explore options, read some more until finally you are posed to ask questions that will lead you quickly toward the right solution for your project. Without this background, your questions will often be wild, untamed and often just not very constructive to you and your colleague.

1.5 GENERAL APPLICATIONS

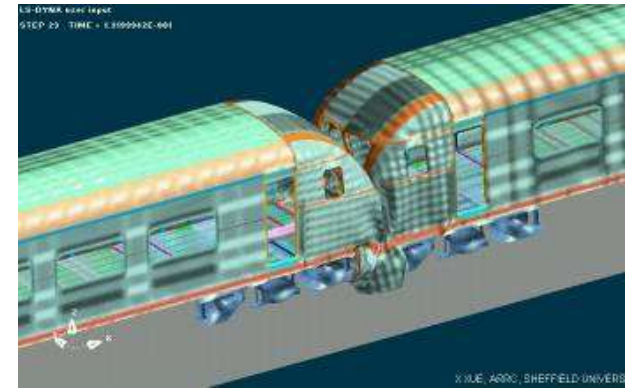
Crashworthiness



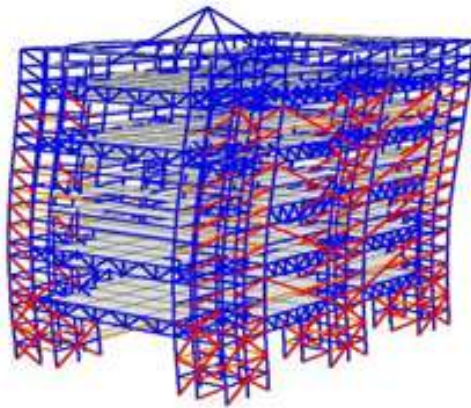
Driver Impact



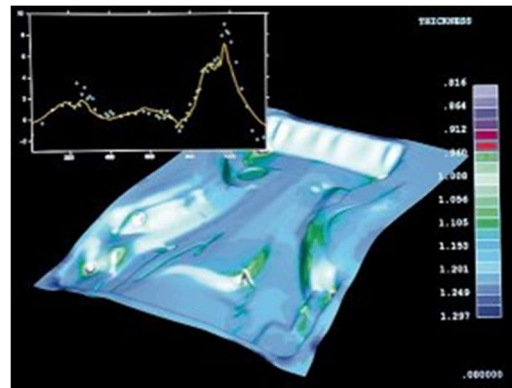
Train Collisions



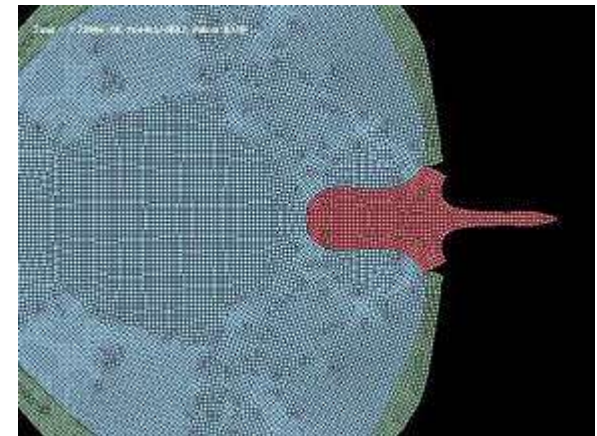
Earthquake Engineering



Metal Forming

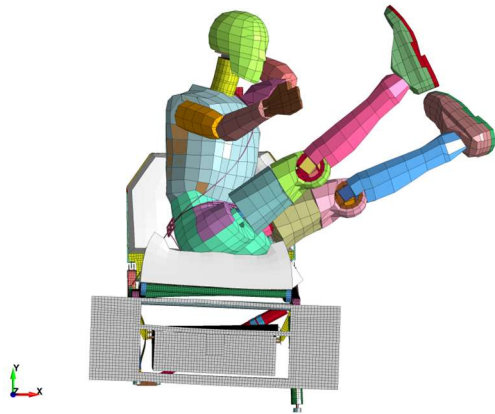


Military

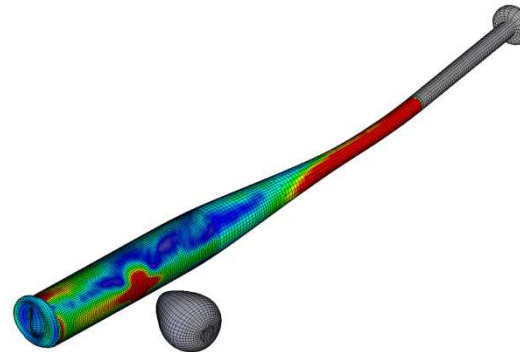


1.6 SPECIFIC APPLICATIONS (COURTESY OF PREDICTIVE ENGINEERING)

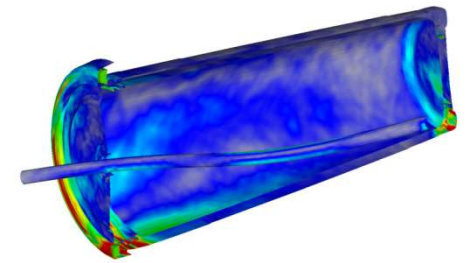
CS-FAR 25 16g Sled Analysis



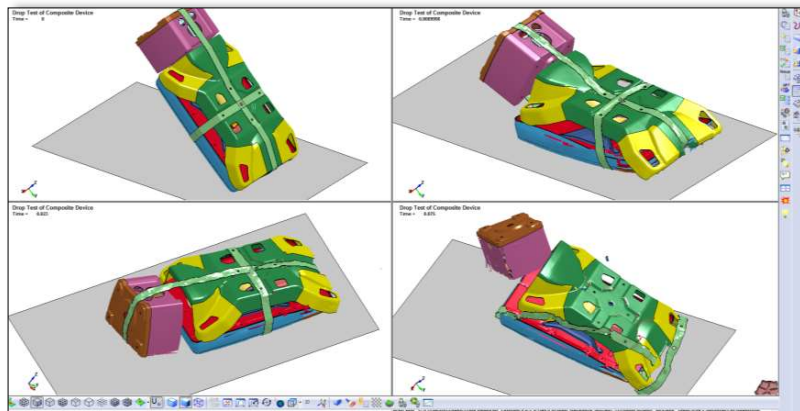
Sporting Goods Equipment



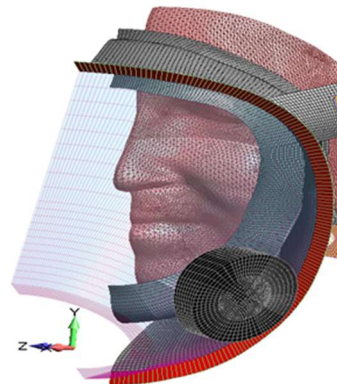
Drop Test Consumer Products



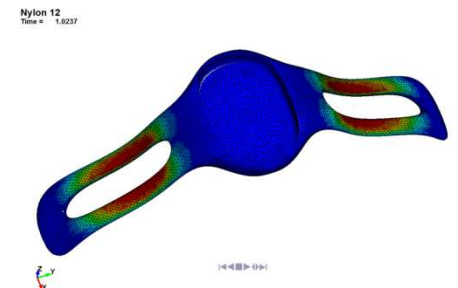
Drop Test of Composites / Electronics



Human Biometrics

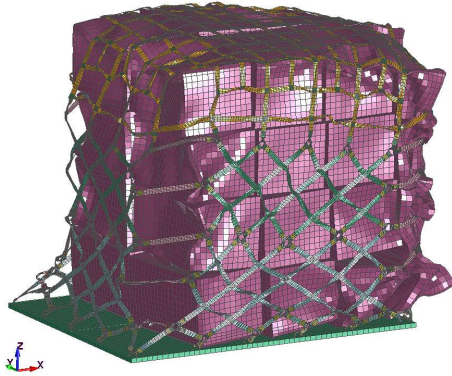


Large Deformation of Plastics

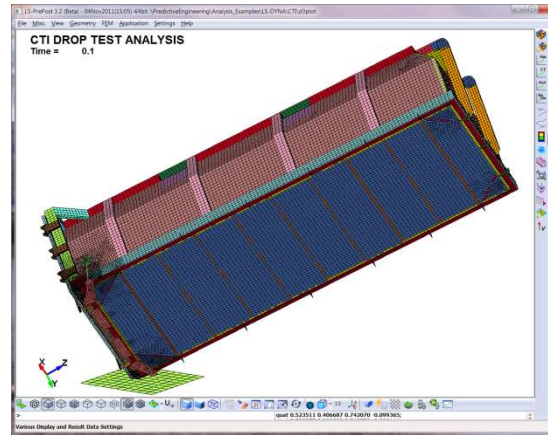


### Crash Analysis of Cargo Net

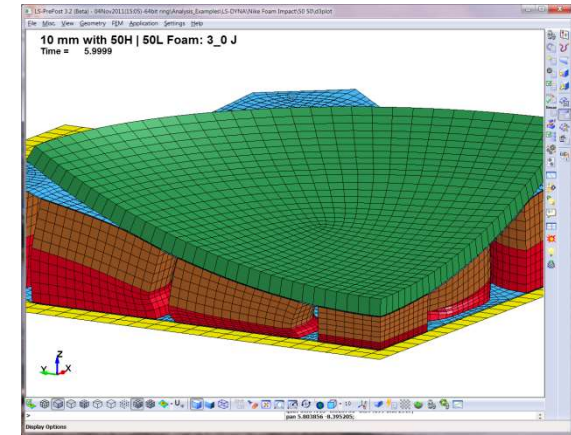
Air Force Cargo Net 9g Crash Simulation  
 Time = 1



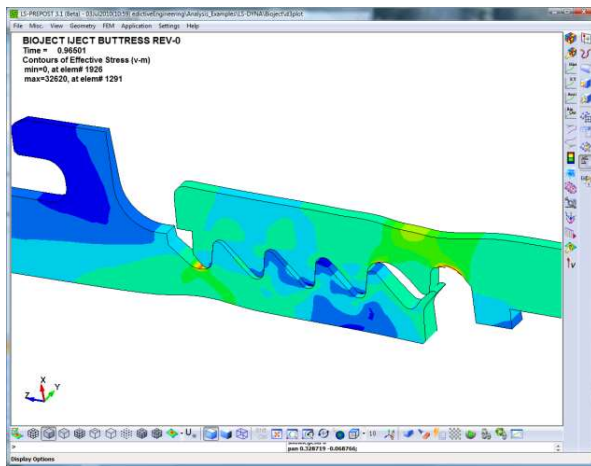
### Drop Test of Nuclear Waste Container



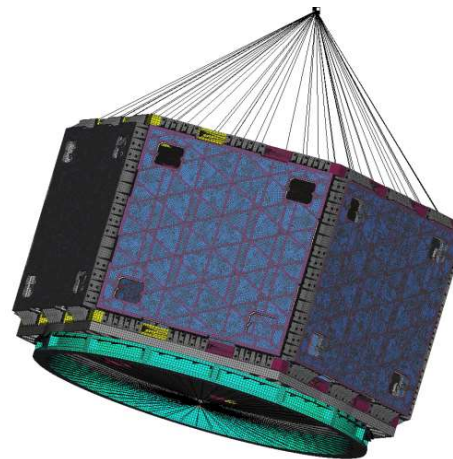
### Impact Analysis of Foams



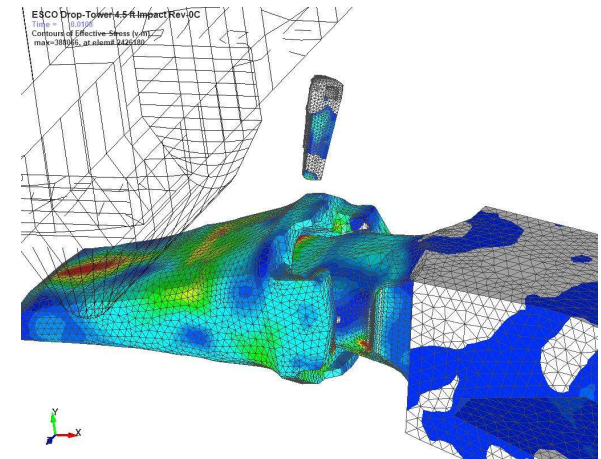
### Plastic Thread Design



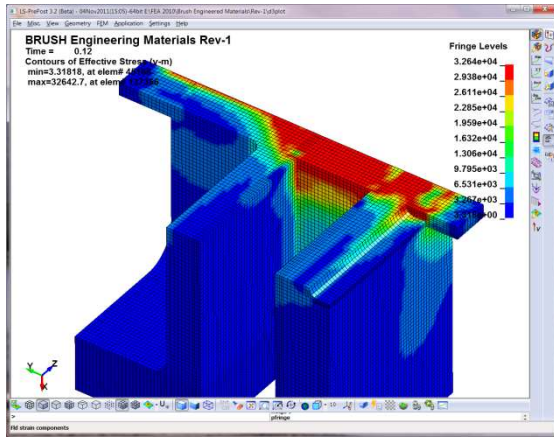
### PSD / Modal Analysis



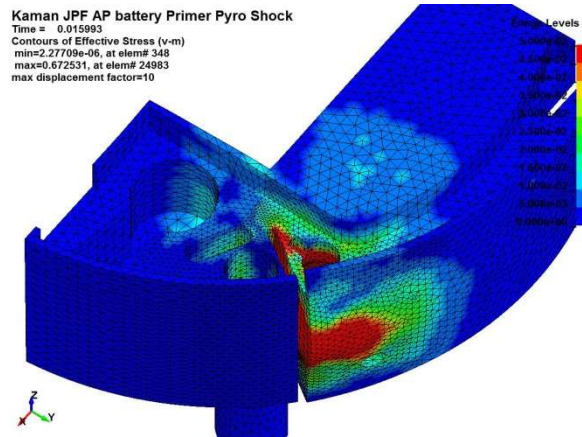
### Digger Tooth Failure



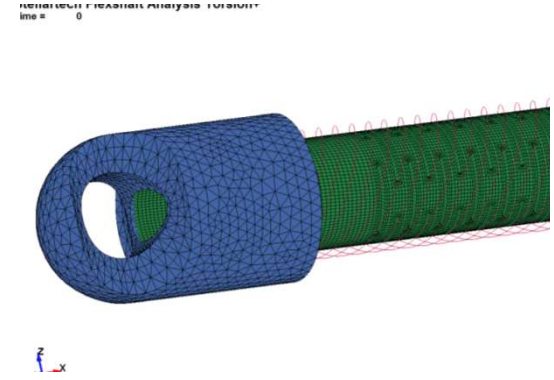
### Electron Beam Welding



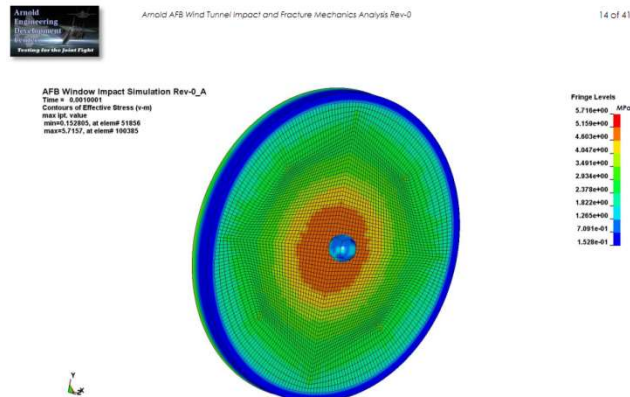
### Pyro-Shock Analysis



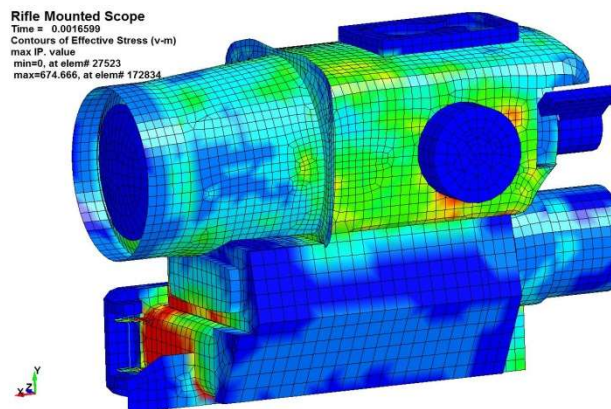
### Medical Equipment



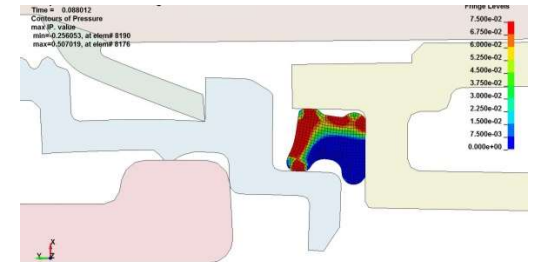
### Fracture Mechanics of Glass



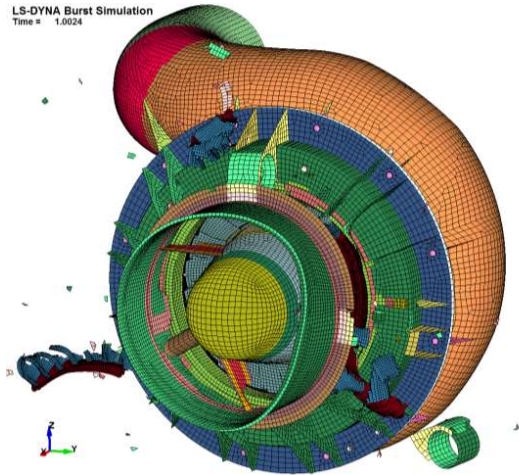
### Ballistic Shock Loading of Optical Equipment



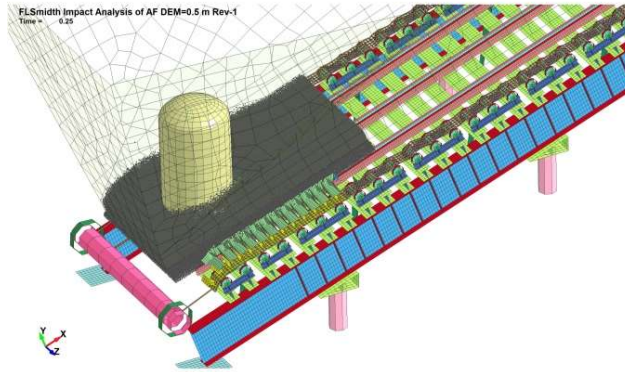
### Hyperelastic Medical Seal Analysis



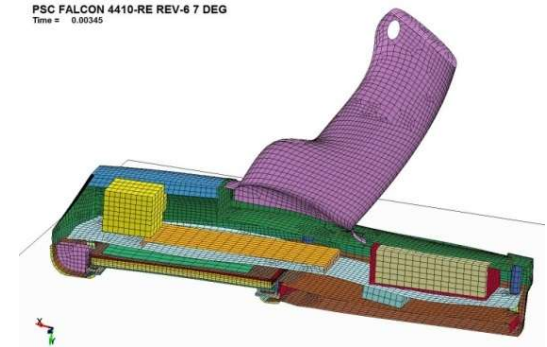
Blade-Out Analysis



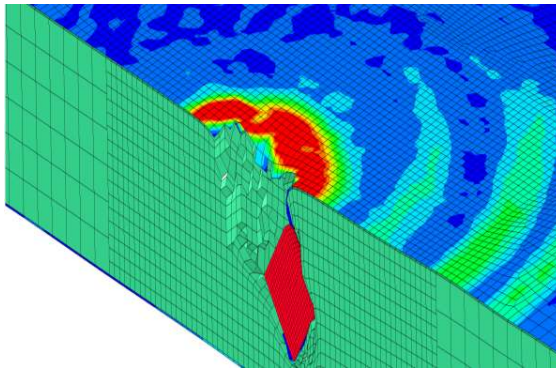
Discrete Element Method for the Mining Industry



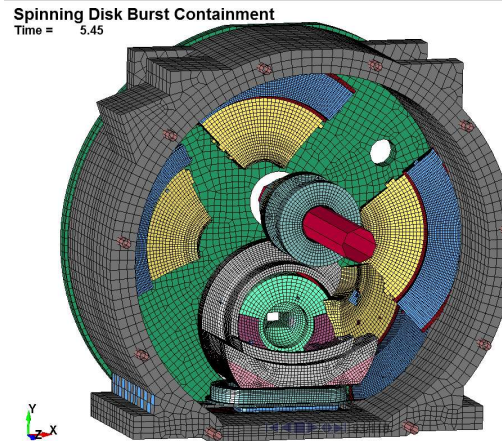
Drop-Test of Handheld Electronics



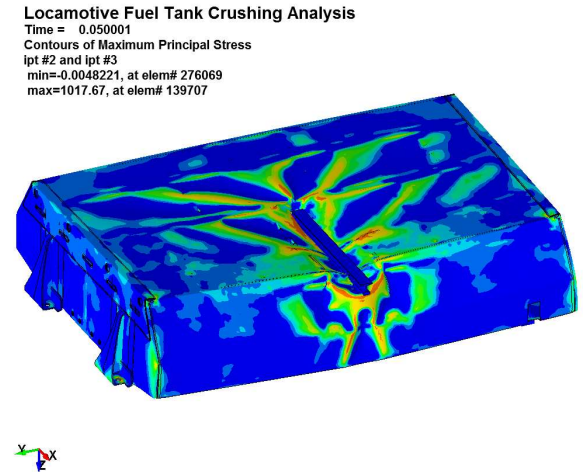
Ballistic Penetration



High-Speed Spinning Disk Containment

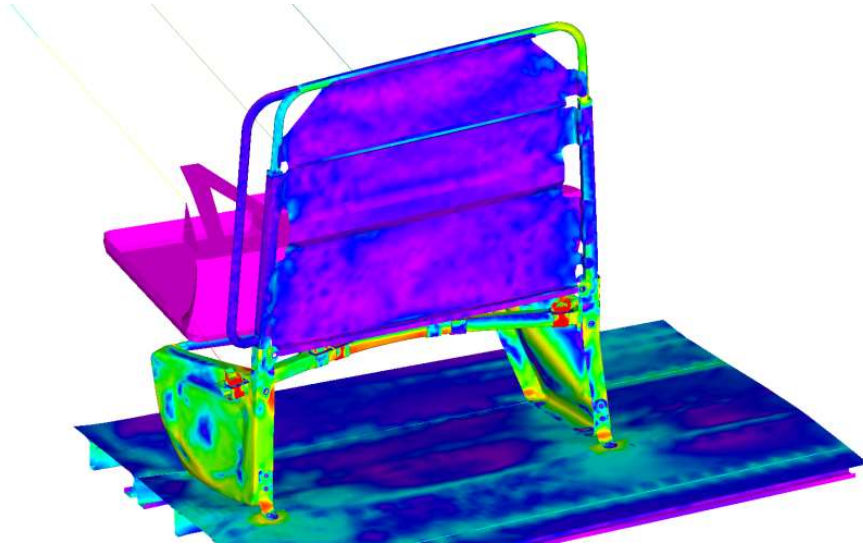


Locomotive Fuel Tank

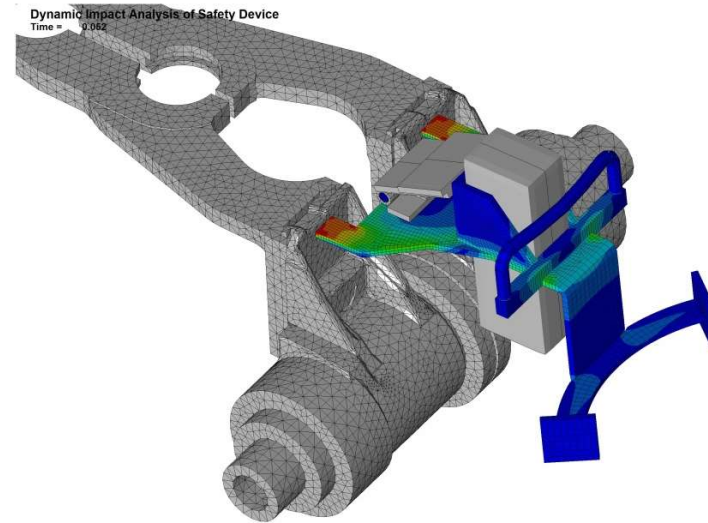




FMVSS Virtual Testing of Bus Seats

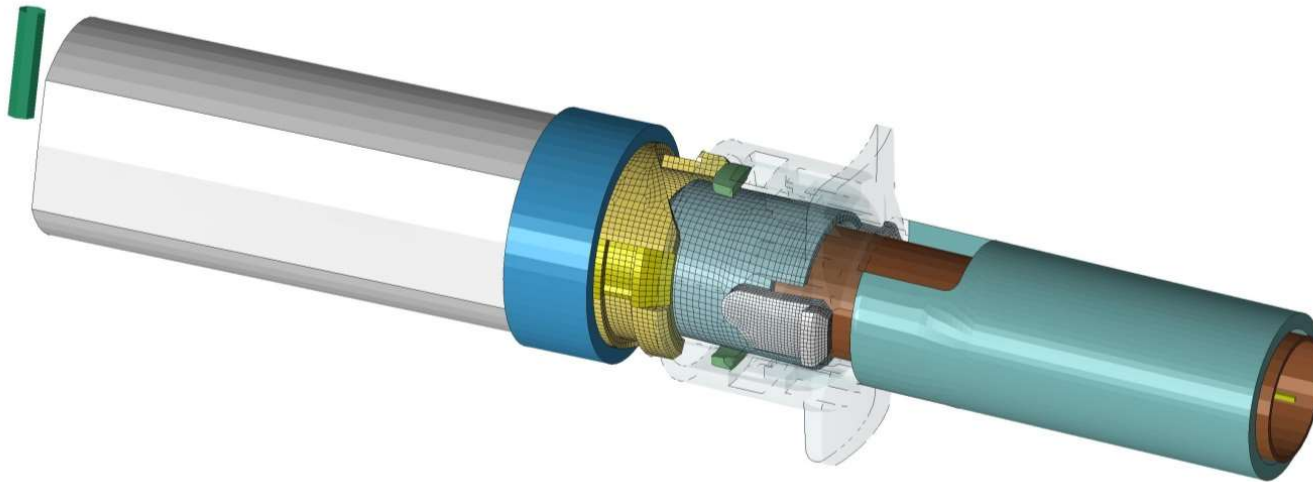


Impact Analysis of Safety Block Device



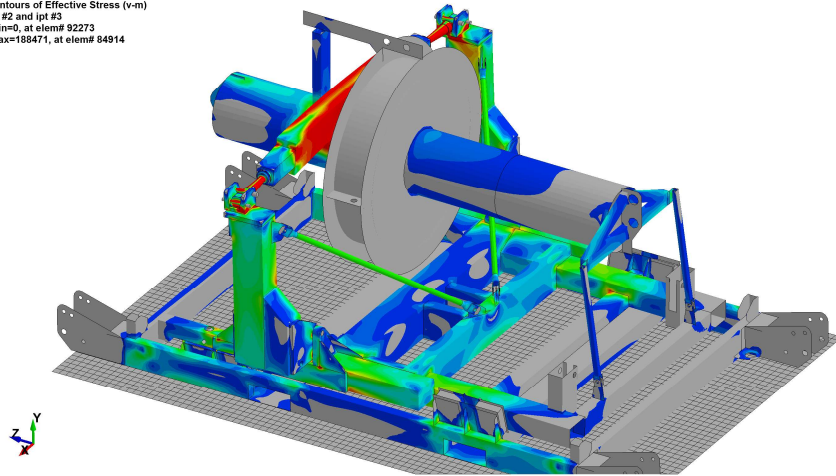
Snap-Fit Analysis – All Plastic Medical Device

Plastic Assembly Snap-Fit  
Time = 12

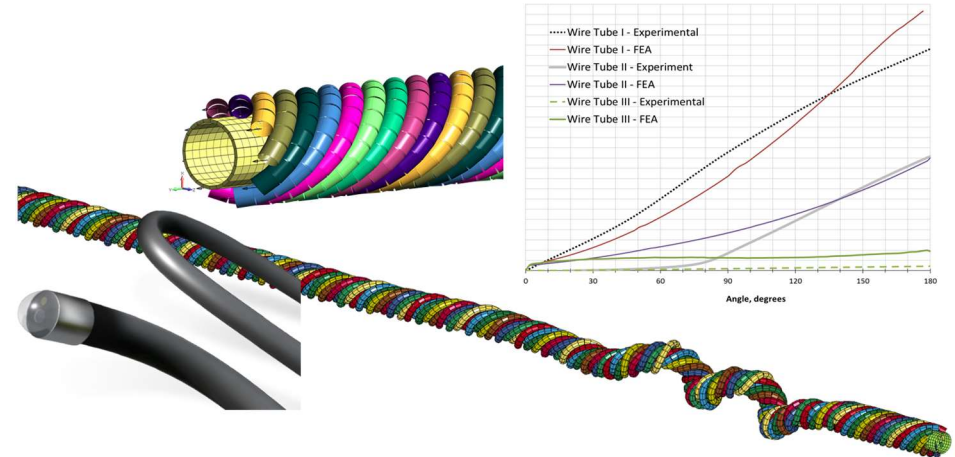


### 9g Crash Analysis of Jet Engine Stand

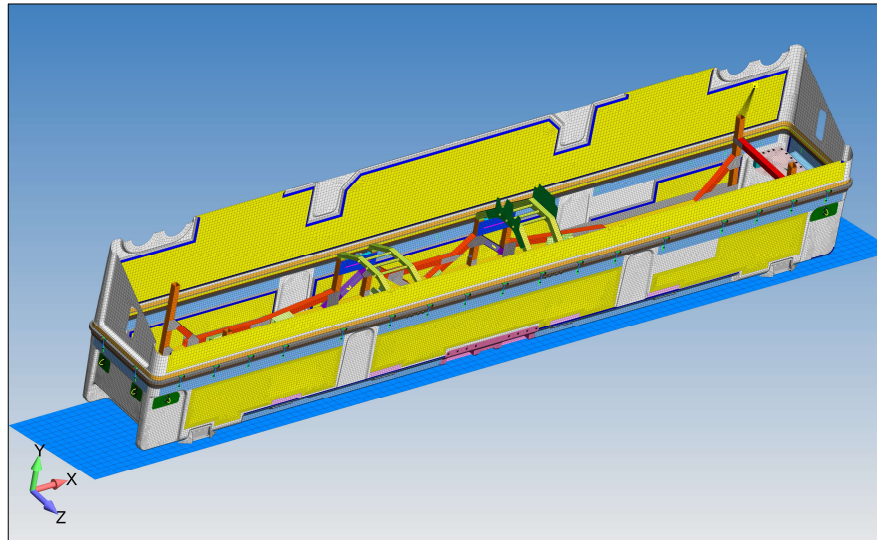
Time = 1.0031  
 Contours of Effective Stress (v-m)  
 ipt #2 and ipt #3  
 min=0, at elem# 92273  
 max=188471, at elem# 84914



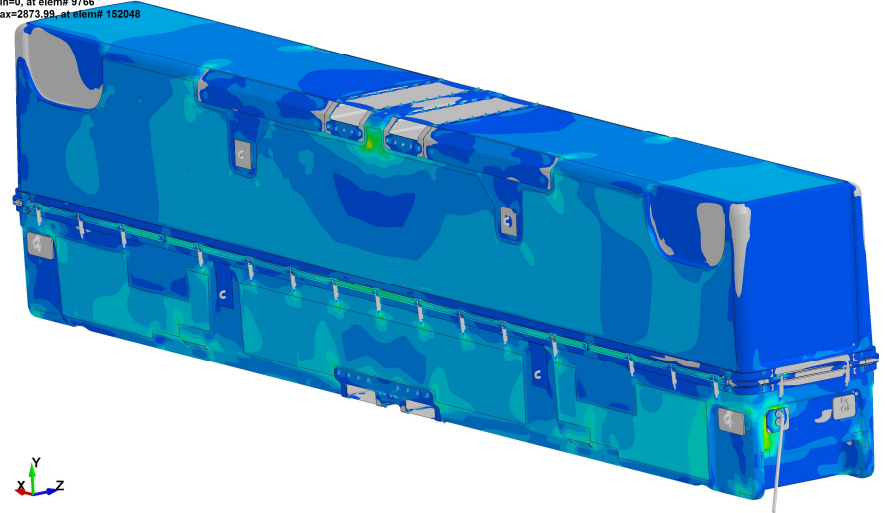
### Torque Analysis of Endoscopic Medical Device



### Drop, Rail Impact and PSD Analysis of Composite Container

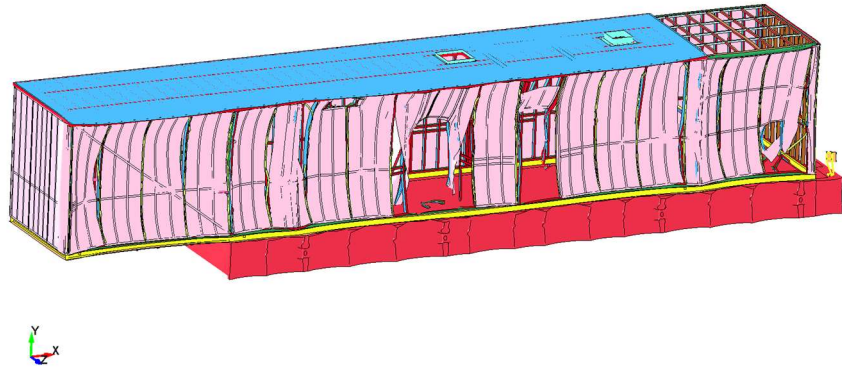


Contours of Effective Stress (v-m)  
 max IP, value  
 min=0, at elem# 9766  
 max=2873.99, at elem# 152048



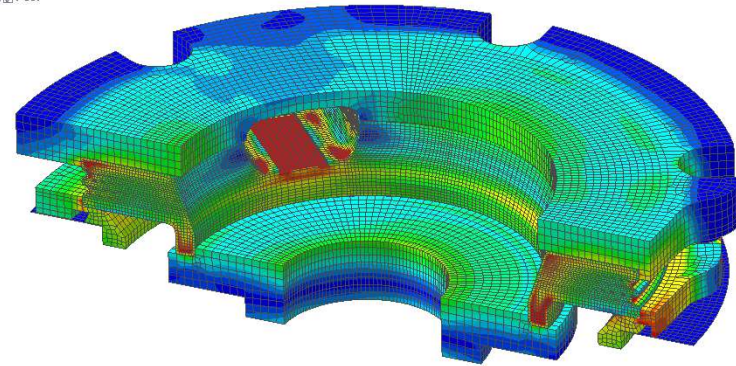
### ConWep Air Pressure Blast Analysis of Generator Housing

LS-DYNA Air Pressure ConWep Blast Analysis Rev-1  
 Time = 0.0225



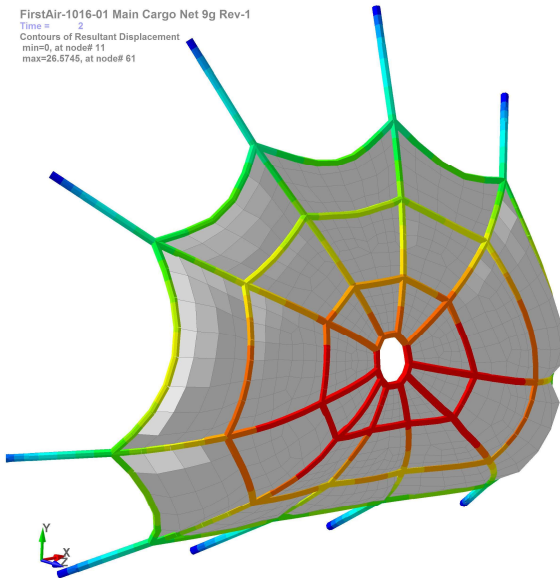
### Alumina-Stainless Steel Braze Process Simulation

FEI-1116-01 Insert F Braze Process Simulation Ambient to Solidus Rev-0  
 Time = 0.68133  
 Contours of Effective Stress (v-m)  
 outer shell surface  
 min=0, at elem# 171025  
 max=80.7882, at node# 243293  
 Effective Str

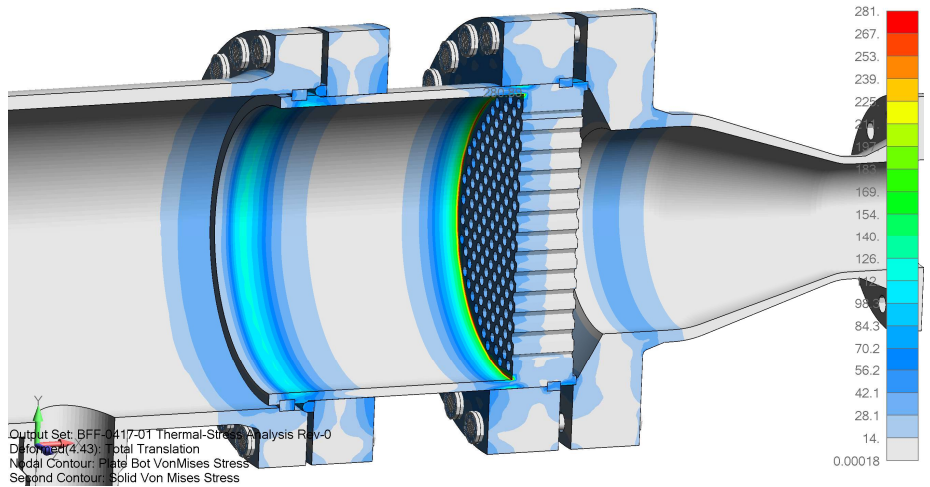


### Air Freighter 9g Cargo Net Analysis

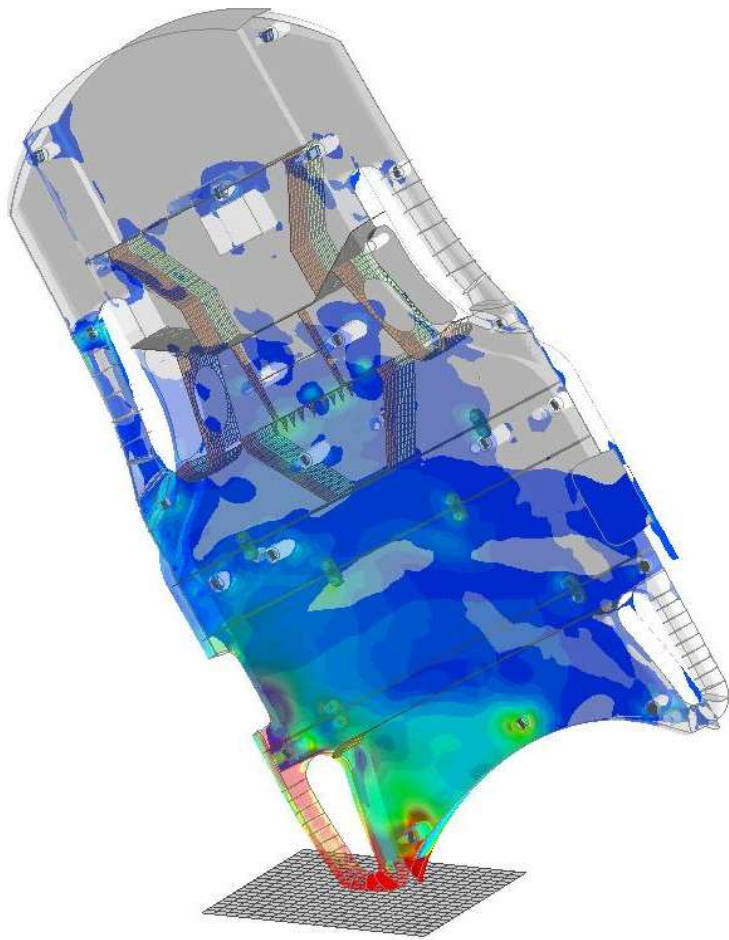
FirstAir-1016-01 Main Cargo Net 9g Rev-1  
 Time = 2  
 Contours of Resultant Displacement  
 min=0, at node# 11  
 max=26.5745, at node# 61



### Thermal-Stress Fatigue Analysis of ASME Evaporator Vessel

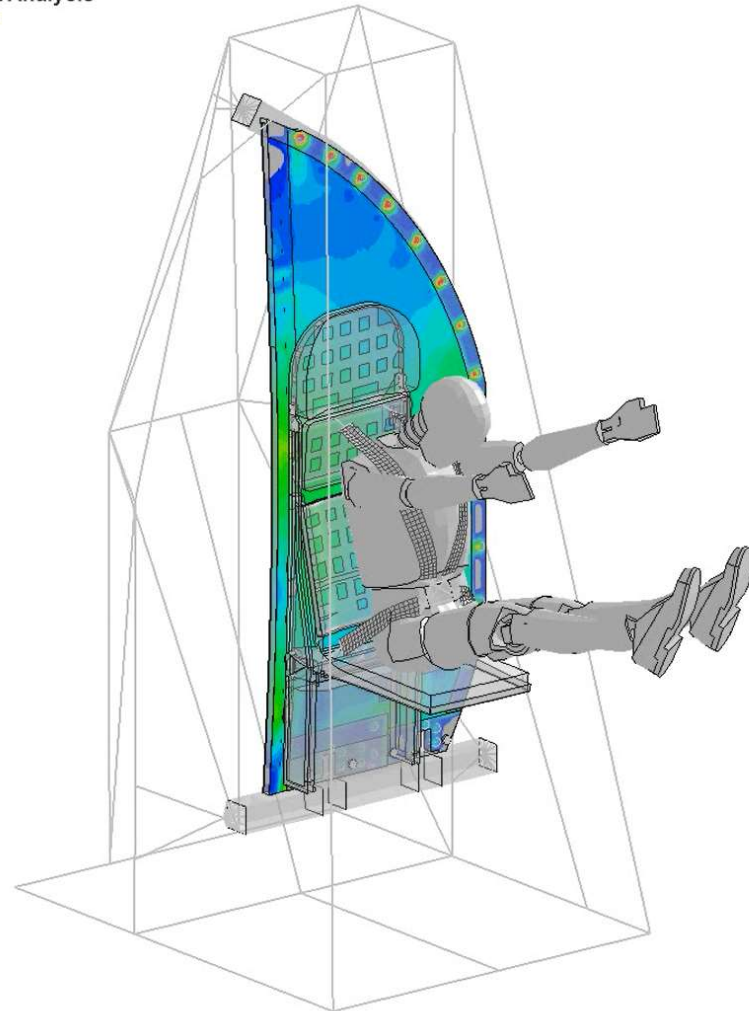


Drop-Test of First-Responder Medical Equipment



Composite Lavatory Wall with Attendant Seat 16g Sled Test

at Analysis  
12



## 2. WHAT IS LS-DYNA?

LS-DYNA is a finite element analysis (FEA) solver. It is the motor that generates results based on what the user provides as input. In other words, it is not a program that generates a mesh or that can create stress contour plots but the world's most sophisticated and complex FEA solver. The workflow is to provide LS-DYNA an ascii text based deck (with a suffix as \*.k or \*.dyn) with nodes, elements, loads, constraints, material laws, etc. and then LS-DYNA solves this input and generates another file (\*.f06) with the requested results.

One can read an LS-DYNA analysis deck with any text editor. A lot of useful information about the LS-DYNA code and its structure can be found in the LS-DYNA Keyword Manual Vol. 1. For every new user, it is time well spent to read the Introduction and Getting Started sections. It provides some very nice background on the LS-DYNA code.

### 2.1 HOW WE VISUALIZE THE LS-DYNA ANALYSIS PROCESS

No matter where you build your deck, LSTC's LS-PrePost (henceforth LSPP) is often an invaluable tool along the way to a validated FEA model. This course is focused on setting up a simulation model that is solvable by LS-DYNA, that will generate results that are verifiable and that will lead to a validated solution. We do not focus on how the nodes and elements are generated within a FEA tool but we do focus on their quality.

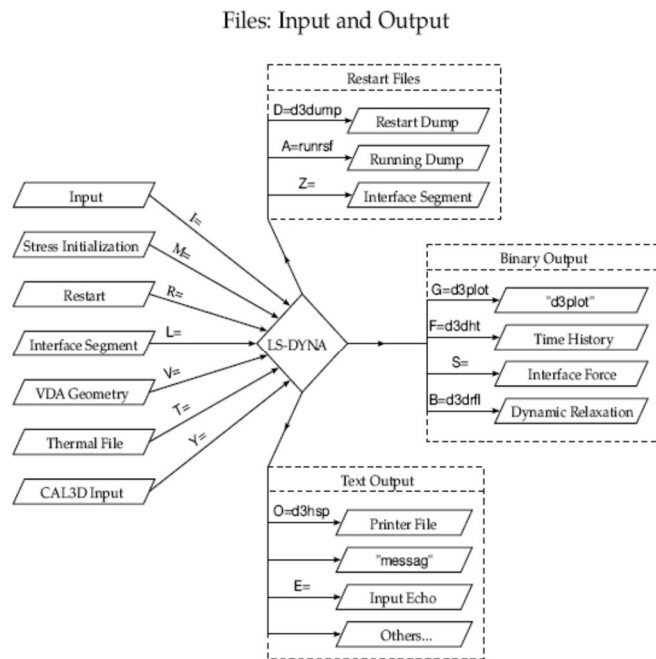


Figure 2-2. Files Input and Output.

Pre-Processor  
 (Nodes, Elements, Etc.)

Commercial Software  
 {Ansys WP, Hypermesh,  
 FEMAP, ANSA, etc.}

*Pre-Processing to Create Keyword Deck*

## LS-DYNA

*Post-Processing FEA Results*

Commercial Software  
 {Ansys WB, Hypermesh, FEMAP,  
 Oasys, etc.}

LSPP

Proprietary Software

### 3. IMPLICIT VERSUS EXPLICIT ANALYSIS

LS-DYNA is a non-linear transient dynamic finite element code with both explicit and implicit solvers.

#### 3.1 WHAT WE ARE SOLVING

Explicit only works when there is acceleration of *mass* (dynamic) whereas an implicit approach can solve the dynamic and the static problem (*no mass*). For dynamic problems, we are solving the following equation:

$$ma^n + cv^n + kd^n = f^n$$

where n=time step. A common terminology is to call the  $kd^n$  part the internal force in the structure. The basic problem is to determine the displacement at some future time or  $d^{n+1}$ , at time  $t^{n+1}$ . However, this is where it gets interesting, explicit is based on acceleration whereas implicit is displacement.

In conceptual terms, the difference between Explicit and Implicit dynamic solutions can be written as:

$$\textit{Explicit: } a^{n+1} = f(d^n, v^n, a^n, d^{n-1}, v^{n-1}, \dots)$$

All these terms are known at time state “n” and thus can be solved directly. This means that the solution marches forward regardless of the element deformation or contact behavior or whatever nonlinearities (*importantly, no residual – see below*). However, it doesn’t mean that it might not blow up if elements get too distorted and it doesn’t mean that contact will always contact.

For *Implicit*, the solution depends on nodal velocities and accelerations at state n+1, quantities which are unknown:

$$\textit{Implicit: } d^{n+1} = f(v^{n+1}, a^{n+1}, d^n, v^n, \dots)$$

Given these unknowns, an iterative solution is required to calculate the displacement at this future time. If the nonlinearity is mild, the implicit approach allows one to use a comparably large time step as that compared to the explicit analysis and the run time can be advantageous. This is because an implicit solution must perform an iterative solution to reduce the residual within each time step:

$$ma^n + cv^n + kd^n - f^n = \textit{Residual}$$

If the nonlinearity is severe, the implicit solution may require a very small time step and a large number of iterations within each step to reduce the residual to something reasonable (i.e., a converged solution). In contrast, an explicit solution has no residual and just solves but requires a small time step (more will be said about this later). Thus, when faced with large nonlinearities, an explicit solution is more robust whereas, if the nonlinearity is mild, an implicit solution is often more practical to get the job done quickly.

### 3.2 EXPLICIT (DYNAMIC) – ONE MUST HAVE “MASS” TO MAKE IT GO

Internal and external forces are summed at each node point, and a nodal acceleration is computed by dividing by nodal mass. The solution is advanced by integrating this acceleration in time. The maximum time step size is limited by the Courant-Friedrichs-Lewy (CFL) criterion (to be discussed). For now let's say that the solution marches forward in time using a fixed time step that is calculated based on the element size and the speed of sound in the material (i.e., CFL). Much more will be said about element size and the speed of sound in materials since execution speed for an explicit analysis is often of great importance given that careful meshing can mean the difference between a run time of days or hours. Just to keep this theme in the forefront of our discussion: an explicit analysis is all about mass since everything has a time step (e.g., contact, 1D spring elements, CNRB's, etc.).

### 3.3 IMPLICIT (DYNAMIC OR STATIC)

A global stiffness matrix is computed, decomposed and applied to the nodal out-of-balance force to obtain a displacement increment. Equilibrium iterations are then required to arrive at an acceptable “force balance”. The advantage of this approach is that time step size may be selected by the user. The disadvantage is the large numerical effort required to form, store, and factorize the stiffness matrix. Implicit simulations therefore typically involve a relatively small number of expensive time steps. The key point of this discussion is that the stiffness matrix (i.e., internal forces) has to be decomposed or inverted each time step whereas in the explicit method, it is a running analysis where the stiffness terms are re-computed each time step but no inversion is required. Since this numerical technique is independent of a time step approach, element size is not of direct concern only the size of the model (nodes/elements) directly affects the run time.

3.3.1 PROS AND CONS OF EXPLICIT V IMPLICIT

Explicit		Implicit	
<b>Pros</b>	<b>Cons</b>	<b>Pros</b>	<b>Cons</b>
It solves directly since the solution marches forward.	Solution time step controlled by wave speed and element mechanics.	Large time steps can be used since the solution is iterative.	Requires iterative process to converge.
Dynamic solution	Long run times for simulations that require long event times.	Static and Dynamic solutions	Requires iterative process to converge which can lead to long run times.
Extreme nonlinearity is easily handled.	Of course, solution can blow up due to twisted elements or contact problems.	Linear and Nonlinear solutions	Implicit struggles with extreme nonlinearity
Pretty much all physics can be solved.	W.R.T. multi-physics, no real cons since you are solving the impossible.	Provides the missing link in LS-DYNA to solve standard linear static and dynamic problems.	Focused on solid mechanics so don't expect to see meshfree methods anytime soon.



## 4. LS-DYNA GETTING STARTED WITH THE FUNDAMENTALS

### 4.1 LS-DYNA KEYWORD MANUAL

LS-DYNA has perhaps one of the most basic learning methods. It is organic. One simply has to dig in and learn the basics and there is no substitute for doing it yourself. The Keyword Manual also provides recommended usage guidelines and examples on how to use the commands. It is your first and best resource. Given the frequency of program updates, the Keyword manuals are likewise being constantly updated. Fairly recent versions of the four Keyword manuals can be found in the *Class Reference Notes / Keyword Manuals*.

*Analyst's Note: Please keep in mind that LS-DYNA is an analysis engine that runs off of an ascii deck (a text file) and that oftentimes the fastest path to an optimum solution is to edit the deck. It took me years to embrace the "deck" and I'm better for it.*

### 4.2 KEYWORD SYNTAX

- Commands are strings of words separated by an underscore, e.g., \*BOUNDARY\_PRESCRIBED\_MOTION\_RIGID.
- Text can be uppercase or lowercase
- Commands are arranged alphabetically in User's Manual
- Order of commands in input deck is **mostly** unimportant (except \*KEYWORD, \*DEFINE\_TABLE (but then one can use \*DEFINE\_TABLE\_2D if this is a problem), \*INCLUDE\_TRANSFORM, ?)
- Keyword command must be left justified, starting with an asterisk
- A "\$" in the first column indicates a comment
- If one would like to screen print out comments, use \*COMMENT
- Input values (card data) can be *anywhere within fixed fields or/and comma-delimited* (Although one will notice that I like to right-justify values within fixed fields but it is not necessary.)
- A blank parameter indicates that the default value of the parameter will be used (or taken from \*CONTROL\_option)
- Please keep in mind that every Keyword starts with "\*" and that each line below the Keyword is a "card" per the LST-ANSYS Keyword Manual.

*Analyst's Note: Want more Keyword information – read Appendix V: How to Read Card Summaries. This Appendix explains the philosophy behind the \*KEYWORD structure and its syntax. It should be required reading for any 'DYNA addict.*

## LS-DYNA® KEYWORD USER'S MANUAL

### VOLUME I

03/03/17 (r:8240)  
 LS-DYNA Dev

LIVERMORE SOFTWARE TECHNOLOGY CORPORATION (LSTC)

### Required Commands:

\*KEYWORD  
 \*CONTROL\_TERMINATION  
 \*NODE  
 \*ELEMENT  
 \*SECTION  
 \*MAT  
 \*PART  
 \*DATABASE\_BINARY\_D3PLOT  
 \*END