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Sören Bartels, Tomáš Roubíček

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Sören Bartels1,∗ and Tomáš Roubíček3,4,†

1 Institut für Numerische Simulation, Rheinische Friedrich-Wilhelms-Universität Bonn, Wegelerstraße 6, D-53115 Bonn, Germany
2 Mathematical Institute, Charles University, Sokolovská 83, CZ-186 75 Praha 8, Czech Republic
3 Institute of Information Theory and Automation, Academy of Sciences, Pod vodárenskou věží 4, CZ-182 08 Praha 8, Czech Republic
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Abstract. A viscoelastic solid in Kelvin-Voight rheology involving plasticity coupled with a heat-transfer equation through a temperature-dependent yield stress is investigated. No hardening is studied but the evolution of the plastic strain is considered to be rate-dependent. A numerical scheme which is semi-implicit in time and employs lowest order finite elements on weakly acute triangulations in space is devised and its convergence is proved by careful subsequent limit passage. Computational studies underline robustness and efficiency of the method and illustrate physical effects such as the softening of a material due to dissipated energy that causes a rise in temperature and a local decrease of the yield stress.

Key Words. Thermodynamics of plasticity, temperature dependence of yield stress, Kelvin-Voight rheology, thermal expansion, adiabatic effects.

AMS Subject Classification: 35K85, 49S05, 65M60, 74C10, 80A17.

1. Introduction

Slip plasticity in metals is an activated inelastic process that dissipates mechanical energy to heat and, if hardening effects are considered, also to changes of the internal structure of the material. If not infinitesimally slow or the body is not perfectly isolated, the mentioned heat production leads to temperature changes that may conversely influence the activation threshold (=yield stress) for the plastic material behaviour. In such a way, heat transfer/production and mechanical processes are intimately coupled. We remark that variations of such an activation threshold may be very significant, e.g., in steel products manufacturing it may easily vary by a ratio of 5:1 or more when the temperature ranges about 1000°C.

There is an extensive engineering literature addressing thermoplasticity and advocating computationally sophisticated models, see, e.g., [2, 6, 13, 20, 23, 30]. Mathematically supported theories seem unavailable except for an efficient hysteresis-operator approach
for thermoplastic processes of a one-dimensional character [18, 19] and certain models in [12] considering a temperature-independent yield stress. For the mathematically well understood case of isothermal plasticity we refer the reader to [1, 10, 14, 15, 21] and also [22, Sect. 5.2].

The main mathematical difficulties in the analysis of inelastic material behaviour are related to multiplicative plasticity at finite strains, evolution of even only elastic response if kinetic effects are taken into account, and coupling of rate-independent processes with rate-dependent ones. In fact, each of these issues represents itself a hard open problem, especially in three-dimensional settings and if no regularization (e.g., by capillarity or higher viscosity) is involved. This is why we adopt the following simplifications: small strains and additive plasticity, linear elastic response (so that, in particular, adiabatic effects are suppressed), and rate-dependent plasticity, meaning that fast evolution of plastic strain dissipates (at least slightly) more energy than slow evolution. This additional rate-dependent dissipation is advocated even on microstructural level by rate-dependent evolution of dislocations, cf. [17, Figure 1], and allows us to avoid hardening without creating spatial concentrations of plastic strain as it would be in the case of fully rate-independent plasticity [10] and, most importantly, also awkward interactions of concentrating plastic-strain rates with thermal effects. The mathematical model will be formulated in Section 2 where also its thermodynamics will be addressed.

The main purpose of this paper, performed in Sections 3 and 4, is to develop an implementable numerical scheme for the model and prove its stability, i.e., derive a-priori estimates, and convergence to a suitably defined weak solution of the mathematical model. In Section 5 efficiency of our numerical scheme is demonstrated on a 2D example modeling a practical experiment and exhibiting rate-dependent effects of the thermal coupling known as thermal necking within a fast loading experiment. We will mostly focus on a temperature-independent elastic response, which is eligible when a thermal expansion in the mechanical part is employed and corresponding adiabatic effects in the heat equation can be neglected.

2. THE MATHEMATICAL MODEL

We assume that the physical body under consideration occupies the bounded Lipschitz domain $\Omega \subset \mathbb{R}^d$, $d \leq 3$. The state variables are the displacement $u : \Omega \to \mathbb{R}^d$, the plastic strain $\pi : \Omega \to \mathbb{R}_{\text{sym},0}^{d \times d}$ and the temperature variable $\theta : \Omega \to \mathbb{R}$, where

\begin{align}
\mathbb{R}_{\text{sym},0}^{d \times d} := \{ A \in \mathbb{R}_{\text{sym}}^{d \times d} ; \ \text{tr}(A) = 0 \} \quad \text{and} \quad \mathbb{R}_{\text{sym}}^{d \times d} := \{ A \in \mathbb{R}_{\text{sym}}^{d \times d} ; \ A^\top = A \}.
\end{align}

We consider ideal plastic response determined by a convex, closed neighbourhood $S \subset \mathbb{R}_{\text{sym}}^{d \times d}$ of the origin. The interior of $S$ defines the set of admissible stresses while its boundary is called the yield surface and determines those stresses that trigger the evolution of the plastic strain. We assume that $S$ depends on temperature, i.e., $S = S(\theta)$ for a set-valued mapping $S : \mathbb{R}^+ \rightrightarrows \mathbb{R}_{\text{sym}}^{d \times d}$ qualified below in (3.5d).

Considering a Kelvin-Voigt-type viscous material, our model consists of the equilibrium equation balancing inertial, viscous, and elastic mechanical forces,

\begin{equation}
\varrho \frac{\partial^2 u}{\partial t^2} - \text{div} \left( D \frac{\partial e(u)}{\partial t} \right) - \text{div} (C(e(u) - \pi)) = 0,
\end{equation}

where
the evolution law for the plastic strain $\pi$, modeled with the Prandtl-Reuß flow rule through the inclusion
\begin{equation}
\partial \delta_S^* \left( \frac{\partial \pi}{\partial t} \right) + \mathbb{B} \frac{\partial \pi}{\partial t} - \mathbb{C} (e(u) - \pi) \geq 0,
\end{equation}
and the heat equation
\begin{equation}
c_v \frac{\partial \theta}{\partial t} - \text{div}(\mathbb{K} \nabla \theta) = \delta_S^* \left( \frac{\partial \pi}{\partial t} \right) + \mathbb{B} \frac{\partial \pi}{\partial t} + \mathbb{D} \frac{\partial e(u)}{\partial t} + \frac{\partial e(u)}{\partial t}.
\end{equation}

Here, "\cdot" denotes the product of two $d \times d$-tensors, $e(u)$ is the small-strain tensor
\begin{equation}
e_{ij}(u) := \frac{1}{2} \left( \frac{\partial u_i}{\partial x_j} + \frac{\partial u_j}{\partial x_i} \right),
\end{equation}
and $\delta_S : \mathbb{R}^{3 \times 3} \to \{0, +\infty\}$ is the indicator function of $S$ with conjugate $\delta_S^*$ defined through the duality pairing $s : e = \sum_{i,j=1}^3 s_{ij} e_{ij}$. The subdifferential (i.e., the normal cone) of $\delta_S^*$ is denoted $\partial \delta_S^*$. Moreover, $\mathbb{C} = [C_{ijkl}] \in \mathbb{R}^{d \times d \times d \times d}$ is a positive-definite 4th-order tensor of elastic moduli satisfying the symmetries $C_{ijkl} = C_{klij} = C_{jikl}$. Similarly, $\mathbb{D} \in \mathbb{R}^{d \times d \times d \times d}$ are symmetric, positive-definite fourth-order tensors determining viscous moduli and the rate-dependent part of plastic-strain response, respectively. The symmetric, positive-definite second-order tensor $\mathbb{K} \in \mathbb{R}^{d \times d}$ models heat conductivities while the real numbers $\varrho$ and $c_v$ define the mass density and the heat capacity of the material, respectively.

We remark that the physical dimension of the stress/strain pairing $s : e = \sum_{i,j=1}^3 s_{ij} e_{ij}$ is $\text{Pa} = \text{J/m}^3$ so that $S$ determines the degree-1 homogeneous “plastic” dissipation potential $\delta_S^*$ which acts on the dimensionless tensor $\pi$ and has the dimension $\text{J/m}^3$. The set $S(\theta)$ need not be bounded but should be the direct sum of a closed convex set $S_0(\theta) \subseteq \mathbb{R}_{\text{sym},0}^{d \times d}$ containing the origin and the orthogonal complement of the $\frac{1}{2} d (d+1) - 1$ dimensional space $\mathbb{R}_{\text{sym},0}^{d \times d}$. In other words, $S_0(\theta)$ contains all matrices whose deviator belongs to a given convex set. This ensures that $\delta_S^* \in \mathbb{R}_{\text{sym},0}^{d \times d}$.

We consider Dirichlet boundary conditions on the nonempty, open part $\Gamma_0$ of the boundary $\Gamma := \partial \Omega$ and a mechanical loading defined by a time-varying surface force $g$ acting on another open part $\Gamma_1 \subset \Gamma$. We assume that $\Gamma_0 \cap \Gamma_1 = \emptyset$ and that $\Gamma_0 \cup \Gamma_1$ covers $\Gamma$ up to a set of zero surface measure. We allow heat transfer through $\Gamma$ described by a heat-transfer coefficient $\alpha \geq 0$ and a prescribed heat flux $f$. This corresponds to the boundary conditions
\begin{align*}
u |_{\Gamma_0} &= u_D & &\text{on } \Gamma_0, \\
\left( \mathbb{D} \frac{\partial e(u)}{\partial t} + \mathbb{C} (e(u) - \pi) \right) \nu &= g & &\text{on } \Gamma_1, \\
(\mathbb{K} \nabla \theta) \cdot \nu + \alpha \theta &= f & &\text{on } \Gamma,
\end{align*}
where "\cdot" denotes the scalar product of two vectors and $\nu$ the outer unit normal on $\Gamma$.

The above equations and inclusion (2.2)–(2.5) are to hold on the space-time domain $Q := (0, T) \times \Omega$ with a fixed time horizon $T > 0$. Thus, we consider an initial-boundary-value problem for the system (2.2)–(2.5) and impose the initial conditions
\begin{equation}
u(0, \cdot) = u_0, \quad \frac{\partial u}{\partial t}(0, \cdot) = \dot{u}_0, \quad \pi(0, \cdot) = \pi_0, \quad \theta(0, \cdot) = \theta_0.
\end{equation}

The energetics of the model problem relates the stored energy
\begin{equation}
\Phi(u, \pi) := \frac{1}{2} \int_\Omega \mathbb{C} (e(u) - \pi) : (e(u) - \pi) \, dx,
\end{equation}
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\begin{equation}
\Phi(u, \pi) := \frac{1}{2} \int_\Omega \mathbb{C} (e(u) - \pi) : (e(u) - \pi) \, dx,
\end{equation}
the **kinetic energy**

\[
T_{\text{kin}}(\dot{u}) := \frac{1}{2} \int_{\Omega} \rho |\dot{u}|^2 \, dx,
\]

the **dissipation rate**

\[
\Xi(\dot{u}, \dot{\pi}) := \int_{\Omega} \delta_{S(\theta)}^* (\dot{\pi}) + B \dot{\pi} : \dot{\pi} + \mathbb{D}(\dot{u}) : e(\dot{u}) \, dx,
\]

the **internal energy**

\[
E(\theta) := \int_{\Omega} c_\theta \theta \, dx,
\]

and the **power of external mechanical forces and heating**

\[
P(t, \dot{u}, \sigma^{\text{nor}}, \theta) := \left\langle \sigma^{\text{nor}}, \frac{\partial u}{\partial t} \right\rangle_{\Gamma_0} + \int_{\Gamma_1} g(t, x) \cdot \dot{u}(x) \, dS + \int_{\Gamma} (f - \alpha \theta) \, dS,
\]

where \(\sigma^{\text{nor}}\) denotes the **normal stress** which is in duality with \(\frac{\partial u}{\partial t}\) and defined by

\[
\left\langle \sigma^{\text{nor}}, \nu \right\rangle_{\Gamma_0} = \left\langle \rho \frac{\partial^2 u}{\partial t^2}, \nu \right\rangle_{\Gamma_0} + \int_{\Omega} \mathbb{D}(u) : e(\nu) \, dx
\]

\[+ \int_{\Omega} C(e(u) - \pi) : e(\nu) \, dx - \int_{\Gamma_1} g(t) \cdot \nu \, dS.
\]

for every \(v \in W^{1/2,2}(\Gamma_0; \mathbb{R}^d)\) with (arbitrary) extension \(\nu \in W^{1,2}(\Omega; \mathbb{R}^d)\). The **energy balance** of the model (2.2)–(2.4) is then obtained by testing (2.2), (2.3), and (2.4) respectively by the velocity \(\frac{\partial u}{\partial t}\), by the plastic strain rate \(\dot{\varepsilon}_p\), and by 1, which gives, after application of Green’s formula for both (2.2) and (2.4) together with the boundary conditions (2.6) and the identity \(\frac{\partial \pi}{\partial t} : \partial S_{\theta}(\dot{\pi}) = \delta_{S(\theta)}(\frac{\partial \pi}{\partial t})\) (cf. (3.3) below),

\[
\frac{d}{dt} \left( T_{\text{kin}}(\frac{\partial u}{\partial t}) + \Phi(u, \pi) + E(\theta) \right) = P(t, \frac{\partial u}{\partial t}, \sigma^{\text{nor}}).
\]

Integrating over \((0, t)\) and introducing the total energy \(T_{\text{kin}}(\dot{u}) + \Phi(u, \pi) + E(\theta) =: E_{\text{tot}}(u, \pi, \theta, \dot{u})\), the energy balance can be written as

\[
E_{\text{tot}}(u(t, \cdot), \pi(t, \cdot), \theta(t, \cdot), \frac{\partial u}{\partial t}(t, \cdot)) - E_{\text{tot}}(u_0, \pi_0, \theta_0, \dot{u}_0)
\]

\[= \int_0^t P(r, \frac{\partial u}{\partial t}(r, \cdot), \sigma(r, \cdot)) \, dr,
\]

which says that the difference of total energies at time \(t\) and at the initial time equals the work done by external forces within the time interval \((0, t)\).

**Remark 2.1.** (Thermodynamics of the model.) One can derive the above model from the **free energy**

\[
\psi(u, \pi, \theta) = \frac{1}{2} C(e(u) - \pi) : (e(u) - \pi) + c_\theta \theta \ln \left( \frac{\theta}{\theta_0} \right)
\]

in which \(\theta_0\) plays the role of a reference temperature. Then, entropy is given by \(s := -\frac{\partial \psi}{\partial \theta} = c_\theta (1 + \ln(\theta/\theta_0))\) and (2.4) can be written in the form of the **entropy equation** as

\[
\theta \frac{\partial s}{\partial t} - \text{div}(K \nabla \theta) = \xi \quad \text{with} \quad \xi := \delta_{S(\theta)}^* \left( \frac{\partial \pi}{\partial t} \right) + B \frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} + \mathbb{D}(e(u)) : \frac{\partial e(u)}{\partial t}.
\]
Note that \( \int_{Q} \xi \, dx = \Xi_{\theta}(\partial_{\theta} \xi, \partial_{\theta} \pi) \) with \( \Xi_{\theta} \) from (2.10). At least formally, assuming positivity of temperature and realizing that \( \xi \geq 0 \), we deduce that the **Clausius-Duhem inequality**

\[
\frac{d}{dt} \int_{Q} s \, dx = \int_{Q} \left( \text{div}(K \nabla \theta) - \frac{K \nabla \theta \cdot \nabla \theta}{\theta} - \frac{\xi}{\theta} \right) \, dx = \int_{Q} \frac{K \nabla \theta \cdot \nabla \theta}{\theta^2} + \frac{\xi}{\theta} \, dx + \int_{\Gamma} f \, dS \geq 0
\]

holds provided \( f \geq 0 \) and the system is thermally isolated corresponding to \( \alpha = 0 \).

**Remark 2.2.** The mathematical model describes a scenario in which the entire dissipated mechanical energy is transferred into heat. In reality, even without considerable hardening effects, only about 90% goes into heat, e.g., in metals, while in polymers it may be only 60%, cf. [25]. The remaining energy dissipates presumably into the change of structure, acoustic emission, etc. These aspects can partially be incorporated in our model by multiplying the right-hand side of the heat equation (2.4) by a non-negative factor not greater than 1. This would make no significant difference in the analysis and implementation below.

### 3. Weak formulation of the model, data qualification

Throughout, we abbreviate \( I := (0, T) \), \( Q := I \times Q \), \( \Sigma := I \times \Sigma \), \( \Sigma_{0} := I \times \Sigma_{0} \), and \( \Sigma_{1} := I \times \Sigma_{1} \). We use the standard notation \( C^{\infty}(:, \mathbb{R}^{d}) \) for the space of smooth \( \mathbb{R}^{d} \)-valued functions, \( L^{p}(:, \mathbb{R}^{d}) \) for \( p \)-th power Lebesgue integrable functions and \( W_{\cdot}^{k,p}(\cdot \times \Sigma_{0}) \) for the Sobolev spaces of functions whose \( k \)-th weak derivatives are in \( L^{p}(:, \mathbb{R}^{d}) \) on the domain indicated. If values range over a Banach space \( \mathbb{X} \), then \( L^{p}(I \times \mathbb{X}) \) refers to the \( L^{p} \)-Bochner space of \( \mathbb{X} \)-valued functions and \( W_{\cdot}^{k,p}(I \times \mathbb{X}) \) is the corresponding Sobolev-Bochner space.

To introduce a suitable definition of a weak solution, we rewrite (2.3) as the system

\[
\begin{align*}
(3.1a) \quad & \omega + B \frac{\partial \pi}{\partial t} - C(e(u) - \pi) = 0, \\
(3.1b) \quad & \omega \in \partial \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right).
\end{align*}
\]

The meaning of \( \omega \) is the **driving stress** for the evolution of the plastic strain. Then, (2.4) can equally be written in the form

\[
(3.2) \quad cv \frac{\partial \theta}{\partial t} - \text{div}(K \nabla \theta) = \omega : \frac{\partial \pi}{\partial t} + B \frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} + D \frac{\partial e(u)}{\partial t} : \frac{\partial e(u)}{\partial t}.
\]

Here we used that for every \( \omega \in \partial \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right) \) we have

\[
(3.3) \quad \omega : \frac{\partial \pi}{\partial t} = \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right).
\]

For a proof of (3.3) notice first that \( \delta_{S(\theta)}^{*}(0) = 0 \) and the definition of \( \partial \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right) \) imply \( \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right) \leq \omega : \frac{\partial \pi}{\partial t} \). The converse inequality follows from \( \delta_{S(\theta)}^{*}(0) = 0 \) and the definition of \( \partial \delta_{S(\theta)}^{*}(0) \), i.e., for every \( \xi \in \partial \delta_{S(\theta)}^{*}(0) = S(\theta) \) we have

\[
(3.4) \quad \xi : \frac{\partial \pi}{\partial t} = \delta_{S(\theta)}^{*}(0) + \xi : \left( \frac{\partial \pi}{\partial t} - 0 \right) \leq \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right).
\]

Since \( \partial \delta_{S(\theta)}^{*} \left( \frac{\partial \pi}{\partial t} \right) \subseteq S(\theta) \) we deduce that (3.4) also holds with \( \xi = \omega \).
To introduce the notion of a very weak solution of the model, we impose the following data qualification:

\[(3.5a) \quad \Omega \text{ a bounded Lipschitz domain in } \mathbb{R}^d \text{ such that there exists an acute triangulation of } \Omega,\]

\[(3.5b) \quad \Gamma_0, \Gamma_1 \text{ polyhedral subsets of } \Gamma = \partial \Omega,\]

\[(3.5c) \quad \mathbb{B}, \mathbb{C}, \mathbb{D} \in \mathbb{R}^{d \times d \times d} \text{ and } \mathbb{K} \in \mathbb{R}^{d \times d} \text{ positive definite tensors satisfying} \]

\[\mathbb{B}_{ijkl} = \mathbb{B}_{jilk}, \quad \mathbb{C}_{ijkl} = \mathbb{C}_{klij}, \quad \mathbb{D}_{ijkl} = \mathbb{D}_{jikl}, \quad \mathbb{K}_{ij} = \mathbb{K}_{ji},\]

\[(3.5d) \quad S : \mathbb{R}^+ \rightarrow \mathbb{R}^{d \times d} \text{ such that } S(\theta) = \Upsilon(\theta)S_0 \text{ for } S_0 \subset \mathbb{R}^{d \times d} \text{ such that} \]

\[S_0 = S_{0,0} + \left\{ \alpha \mathbf{I}_{d \times d} : \alpha \in \mathbb{R} \right\} \text{ with } 0 \in S_{0,0} \subseteq \mathbb{R}_{\text{sym},0}^{d \times d} \text{ closed and convex and } \Upsilon : \mathbb{R}^+ \rightarrow \mathbb{R}^+ \text{ continuous, bounded, and inf } \Upsilon(\cdot) > 0,\]

\[(3.5e) \quad g, c_v, \kappa > 0, \quad \alpha \in W^{1-1/d-\epsilon,d+\epsilon}(\Gamma), \quad \epsilon > 0, \quad \alpha \geq 0,\]

\[(3.5f) \quad f \in L^1(\Sigma), \quad f \geq 0,\]

\[(3.5g) \quad g \in L^2(I; L^q(\Gamma; \mathbb{R}^d)) \quad \text{with } q > \frac{2 - \frac{2}{d}}{d} \text{ for } d \geq 2 \text{ or } q = 1 \text{ for } d = 1,\]

\[(3.5h) \quad u_D = \mathbf{u}_D|_{\Sigma_0} \in W^{1,1}(I; W^{1/2,2}(\Omega; \mathbb{R}^d)) \text{ for } \mathbf{u}_D \in W^{2,1}(I; L^2(\Omega; \mathbb{R}^d)),\]

\[(3.5i) \quad u_0 \in W^{1,2}(\Omega; \mathbb{R}^d),\]

\[(3.5j) \quad \hat{u}_0 \in L^2(\Omega; \mathbb{R}^d),\]

\[(3.5k) \quad \pi_0 \in L^2(\Omega; \mathbb{R}_{\text{sym},0}^{d \times d}),\]

\[(3.5l) \quad \theta_0 \in L^1(\Omega).\]

While every bounded Lipschitz domain in \(\mathbb{R}^2\) with polygonal boundary can be triangulated with triangles whose inner angles are bounded by 90°, it is not clear that every bounded Lipschitz domain in \(\mathbb{R}^3\) with polyhedral boundary admits triangulations into tetrahedra such that every angle between two faces that belong to the same tetrahedron is bounded by 90°. The results in [16] allow to refine an acute triangulation in such a way that the resulting triangulation is acute, too. Therefore, assumption (3.5a) guarantees that there exists a sequence of acute triangulations with arbitrarily small mesh-size. The assumption (3.5d) simplifies our convergence analysis below: if \(\theta_k \rightarrow \theta\) pointwise almost everywhere in \(\Omega\) then any \(w \in L^p(\Omega; \mathbb{R}^{d \times d})\) satisfying \(w \in \partial \delta^\ast_{S(\theta)}(z)\) can be approximated by a sequence \(\{w_k\}_k\) such that \(w_k \in \partial \delta^\ast_{S(\theta_k)}(z)\), e.g., for every \(1 \leq q < p\) we have

\[(3.6) \quad w_k := \frac{\Upsilon(\theta_k)}{\Upsilon(\theta)} w \rightarrow w \quad \text{in } L^q(\Omega; \mathbb{R}^{d \times d}).\]

For a proof of (3.6) notice that \(w \in \partial \delta^\ast_{S(\theta)}(z)\) and \(\partial \delta^\ast_{S(\theta)}S_0(z) = \Upsilon(\theta)\partial \delta^\ast_{S_0}(z)\) so that

\[(3.7) \quad w_k \in \frac{\Upsilon(\theta_k)}{\Upsilon(\theta)} \partial \delta^\ast_{S(\theta_k)}(z) = \frac{\Upsilon(\theta_k)}{\Upsilon(\theta)} \partial \delta^\ast_{S(\theta)}S_0(z) = \Upsilon(\theta_k)\partial \delta^\ast_{S_0}(z) = \partial \delta^\ast_{S(\theta_k)}(z)\]

and \(\Upsilon(\theta_k) \rightarrow \Upsilon(\theta)\) in \(L^r(\Omega)\) for every \(1 \leq r < \infty\). Such a simple approximation would not hold if, e.g., we had assumed merely \(S(\theta_k) \rightarrow S(\theta)\) in a Hausdorff metric on \(\mathbb{R}^{d \times d}\). Of course, (3.5d) restricts generality because the yield surface has always the same shape varying only with temperature. Other plastic material laws would require more sophisticated approximation arguments.
The qualification (3.5e) implies that is α continuous but, in fact, modifications for α only piecewise continuous with possible jumps that are compatible with employed triangulations would also be possible.

The very weak formulation of (2.2)–(2.4) is obtained by standard procedure: we multiply (2.2), (2.4), and (3.1a) by test functions and use Green’s formula and by-part integration in time for both (2.2) and (3.2) together with the boundary and initial conditions (2.6)–(2.7) and the identity σ : ∇z = σ : e(z) if σ is symmetric.

**Definition 3.1. (A very weak formulation.)** We call the triple \((u, \pi, \theta)\) with

\[
\begin{align*}
(3.8a) \\ u & \in W^{1,2}(I; W^{1,2}(\Omega; \mathbb{R}^d)) \\
(3.8b) \\ \pi & \in W^{1,2}(I; L^2(\Omega; \mathbb{R}_0^{d \times d})) \\
(3.8c) \\ \theta & \in L^{d+1, \frac{d+2}{d+1}}(\Omega; \mathbb{L}^{d+1, \frac{d+2}{d+1}}) \cap L^\infty(I; L^1(\Omega)) \quad \text{with any } 0 < \delta \leq \frac{1}{d+1},
\end{align*}
\]

a very weak solution of (2.2) and (3.1)–(3.2) with the initial conditions (2.7) and a very weak solution of (3.10) and (3.13) and perform a successive limit passage.

We remark that since \(\delta^*_{S(\theta(t,x))}\) is a proper convex function on \(\mathbb{R}^{d \times d}\), its subdifferential has a maximal monotone graph in \(\mathbb{R}^{d \times d} \times \mathbb{R}^{d \times d}\) whose inversion \([\partial \delta^*_{S(\theta(t,x))}]^{-1} = \partial \delta_{S(\theta(t,x))} = N_{S(\theta(t,x))}\) is the normal-cone set-valued mapping for almost every \((t, x) \in Q\). The maximal monotonicity is inherited by the graph induced on \(L^2(Q; \mathbb{R}^{d \times d}) \times L^2(Q; \mathbb{R}^{d \times d})\), and thus (3.12) is an equivalent formulation of the inclusion (3.1b), i.e., \(\omega \in \partial \delta^*_{S(\theta)}(\frac{\partial}{\partial t} \pi)\), cf., e.g., [26].

**4. Existence of solutions and their numerical approximation**

In this section we devise a numerical scheme to approximate solutions of the model problem and show that these approximations converge to very weak solutions in the sense of Definition 3.1. To cope with the fact that the right-hand side in the heat equation (2.4) only belongs to \(L^1(\Omega)\), we need to employ two different spatial meshes for the discretization of (3.10) and (3.13) and perform a successive limit passage.
4.1. Triangulations and data approximation. We assume that we are given sequences of regular triangulations \( \{ \mathcal{T}_{h_1} \}_{h_1 > 0} \) and \( \{ \mathcal{T}_{h_2} \}_{h_2 > 0} \) of the polyhedral domain \( \Omega \). We suppose that for each \( h_1 > 0 \) the parts \( \Gamma_0 \) and \( \Gamma_1 \) of \( \Gamma \) are matched exactly by edges (or faces) of elements in \( \mathcal{T}_{h_1} \), that \( h_1, h_2 > 0 \) range over countable sets of positive real numbers with accumulation points at 0, and that \( \max_{K \in \mathcal{T}_{h_j}} \text{diam}(K) \leq h_j \) for \( j = 1, 2 \). Each triangulation \( \mathcal{T}_{h_2} \) is assumed to allow for a discrete maximum principle of the implicitly discretized linear heat equation. If numerical integration is used, then sufficient for this is that \( \mathcal{T}_{h_2} \) is weakly acute if \( d = 2 \) (i.e., the sum of every pair of angles opposite to an inner edge does not exceed 90° whereas angles opposite to boundary edges are bounded by 45°) or strongly acute if \( d = 3 \) (i.e., all angles between faces of tetrahedra are bounded by 45°). We refer the reader to [8, 11, 16, 31] for further details.

We consider \( C^0 \)-conforming \( P_1 \)-elements for the approximation of \( u \) and \( \theta \) and \( P_0 \)-elements for the approximation of \( \pi \) and \( \omega \). The finite-dimensional subspaces of \( L^2(\Omega) \) and \( W^{1,2}(\Omega) \) related to \( P_0 \)- and \( P_1 \)-elements and subordinate to the triangulation \( \mathcal{T}_{h_2} \) respectively by \( V_{0,h_2} \) and \( V_{1,h_2} \). For \( j = 0, 1 \), the \( L^2 \) orthogonal projection onto \( V_{j,h_2} \) is denoted by \( P_{j,h_2} \). We employ numerical integration in \( \Omega \) and on \( \Gamma \) defined through the discrete inner products

\[
(4.1) \quad (\theta, z)_{h_2} := \int_\Omega \mathcal{J}_{h_2}(\theta z) \, dx \quad \text{and} \quad (\theta, z)_{\Gamma,h_2} := \int_\Gamma \mathcal{J}_{h_2}(\theta z) \, dS
\]

for \( \theta, v \in V_{1,h_2} \) and the nodal interpolation operator \( \mathcal{J}_{h_2} : C(\overline{\Omega}) \to V_{1,h_2} \). Standard results on nodal interpolation imply that for \( \theta, v \in V_{1,h_2} \) we have

\[
(4.2) \quad |(\theta, z)_{h_2} - \int_\Omega \theta z \, dx| + |(\theta, z)_{\Gamma,h_2} - \int_\Gamma \theta z \, dS| \leq C_0 h_2 \| \theta \|_{W^{1,2}(\Omega)} \| z \|_{L^2(\Omega)}.
\]

We let \( \tau > 0 \) denote a time-step size satisfying \( T/\tau \in \mathbb{N} \) and define the backward difference operator

\[
(4.3) \quad d_t \phi_k := \tau^{-1}(\phi^k - \phi^{k-1})
\]

for any sequence \( \{\phi^k\}_{k \geq 0} \). We set \( t_k := k\tau \) and

\[
(4.4) \quad X_{h_1,h_2} := V_{1,h_1}^d \times V_{0,h_1}^{d \times d} \times V_{0,h_2} \times V_{1,h_2}
\]

and choose the set of discrete initial data

\[
(4.5) \quad (u_{r_1,h_2}^0, \pi_{r_1,h_2}^0, \omega_{r_1,h_2}^0, \theta_{r_1,h_2}^0) := (P_{1,h_1} u_0, P_{0,h_1} \pi_0, 0, \mathcal{J}_{1,h_1} \theta_0) \in X_{h_1,h_2},
\]

where \( \mathcal{J}_{1,h_1} : L^1(\Omega) \to V_{1,h_1} \) is a non-negativity preserving weak interpolation operator satisfying \( \| \theta_0 - \mathcal{J}_{1,h_1} \theta_0 \|_{L^1(\Omega)} \to 0 \) as \( h_1 \to 0 \), cf., e.g., [24]. We also define \( \dot{u}_{0,h_1} := P_{1,h_1} \dot{u}_0 \in V_{1,h_1} \) and set \( u_{r_1,h_2} := u_{0,h_1} - \tau \dot{u}_{0,h_1} \). Discrete approximations of the given data \( u_D(t_k, \cdot), f_{h_1}(t_k, \cdot) \) and \( g(t_k, \cdot) \) at time level \( t_k \) are defined through

\[
(4.6) \quad u_{D,r_1,h_1}^k := P_{1,h_1} \overline{u}_D(t_k, \cdot) \quad \text{and} \quad f_{r_1,h_1}^k := \left[ f_{h_1} \right]_r^k, \quad g_r^k := \left[ g \right]_r^k,
\]

where \( \overline{u}_D \) refers to (3.5h), \( [v]_r^k(x) := \int_{t_{k-1}}^{t_k} v(t,x) \, dt \), and \( f_{h_1}(t, \cdot) := P_{0,h_1} f(t, \cdot) \) is the \( L^2 \) orthogonal projection of \( f(t, \cdot) \) onto the trace space \( V_{0,h_1} \) of \( \Gamma \).

4.2. Semi-implicit approximation scheme. With the definitions of Subsection 4.1 we define the following semi-implicit in time and finite element in space discretization of (2.2), (3.1)–(3.2).
Algorithm (\(\mathcal{A}\)). Given \(k \geq 1\) and the approximations \((u_{\tau h_1}^{k-1}, \pi_{\tau h_1}^{k-1}, \omega_{\tau h_1}^{k-1}, \theta_{\tau h_1}^{k-1}) \in X_{\tau h_1}\) at level \(k-1\) and \((u_{\tau h_2}^{k-2}, \pi_{\tau h_2}^{k-2}, \omega_{\tau h_2}^{k-2}, \theta_{\tau h_2}^{k-2}) \in X_{\tau h_2}\) at level \(k-2\), compute \((u_{\tau h_1}^{k}, \pi_{\tau h_1}^{k}, \omega_{\tau h_1}^{k}, \theta_{\tau h_1}^{k}) \in X_{\tau h_1}\) such that \(u_{\tau h_1}^{k}|_{\Gamma_0} = u_{\Gamma, \tau h_1}^{k}\) and

\[
\int_\Omega (d^2 u_{\tau h_1}^{k} + z + Dd \pi_{\tau h_1}^{k}) : e(z) + C(e(u_{\tau h_1}^{k}) - \pi_{\tau h_1}^{k}) : e(z)) \, dx = \int_{\Gamma_1} g_\tau^k \cdot z \, dS
\]

for all \(z \in V_{1, \tau h_1}^d\) with \(z|_{\Gamma_0} = 0\),

\[
\omega_{\tau h_1}^{k} + B \pi_{\tau h_1}^{k} - C(e(u_{\tau h_1}^{k}) - \pi_{\tau h_1}^{k}) = 0,
\]

\[
\omega_{\tau h_1}^{k} \in \partial \delta^* S(P_{\tau h_1}^{k-1})(d \pi_{\tau h_1}^{k})
\]

and

\[
\int_\Omega \left( \omega_{\tau h_1}^{k} : d_t \pi_{\tau h_1}^{k} + B \pi_{\tau h_1}^{k} : d_t \pi_{\tau h_1}^{k} + Dd \pi_{\tau h_1}^{k} : d_t e(u_{\tau h_1}^{k}) : d_t e(u_{\tau h_1}^{k}) \right) z \, dx
\]

for all \(z \in V_{1, \tau h_1}\).

Employing two independent sequences of triangulations allows us to use simple triangulations for the nonlinear system (4.7)–(4.9) while the presumably more complicated (weakly) acute triangulation is only required for the linear heat equation (4.10). Algorithm (\(\mathcal{A}\)) is unconditionally well posed as the following proposition shows.

**Proposition 4.1. (Existence of the approximate solution.)** For each \(k = 1, 2, ..., T/\tau\), there exists a unique solution \((u_{\tau h_1}^{k}, \pi_{\tau h_1}^{k}, \omega_{\tau h_1}^{k}, \theta_{\tau h_1}^{k}) \in X_{\tau h_1}\) of the system (4.7)–(4.10) satisfying \(\pi_{\tau h_1}^{k} \in \mathbb{R}^{d \times d}_{\text{sym}}\) almost everywhere in \(\Omega\).

**Proof.** Given \(k \geq 1\), \((u_{\tau h_1}^{k-1}, \pi_{\tau h_1}^{k-1}, \omega_{\tau h_1}^{k-1}, \theta_{\tau h_1}^{k-1}) \in X_{\tau h_1}\), and \((u_{\tau h_2}^{k-2}, \pi_{\tau h_2}^{k-2}) \in V_{\tau h_2}^d\) we first consider the minimization problem

\[
\text{minimize } \int_\Omega \left( \theta - 2u_{\tau h_2}^{k-1} + u_{\tau h_1}^{k-2} \right)^2 + 2\tau \delta^* S(P_{\tau h_1}^{k-1})(\pi - \pi_{\tau h_1}^{k-1}) + \tau B(\pi - \pi_{\tau h_1}^{k-1}) : (\pi - \pi_{\tau h_1}^{k-1}) \, dx + 2\tau^2 \Phi(u, \pi) - 2\tau^2 \int_{\Gamma_1} g_\tau^k \cdot u \, dS
\]

subject to \((u, \pi) \in V_{\tau h_1}^d \times V_{\tau h_2}^d\) and \(u|_{\Gamma_0} = u_{\Gamma, \tau h_1}\),

where \(\Phi\) is defined by (2.8). The existence of a unique solution, denoted \((u_{\tau h_1}^{k}, \pi_{\tau h_1}^{k})\),

(4.11)

(to (4.11) follows from the coercivity and strict convexity of the involved functionals. The corresponding optimality conditions yield (4.7)–(4.9). Noting that \(\pi_{\tau h_1}^{0} \in \mathbb{R}^{d \times d}_{\text{sym}}\) almost everywhere in \(\Omega\) and that \(\delta^* S(P_{\tau h_1}^{k-1})\) is finite only on \(\mathbb{R}^{d \times d}_{\text{sym}}\), we argue by induction to deduce that \(\pi_{\tau h_1}^{k} \in \mathbb{R}^{d \times d}_{\text{sym}}\) almost everywhere in \(\Omega\). The solution \((u_{\tau h_1}^{k}, \pi_{\tau h_1}^{k})\) defines \(\omega_{\tau h_1}^{k}\) as in (4.9) and we introduce the discrete dissipation term

\[
\xi_{\tau h_1}^{k} := \omega_{\tau h_1}^{k} : d_t \pi_{\tau h_1}^{k} + B \pi_{\tau h_1}^{k} : d_t \pi_{\tau h_1}^{k} + Dd \pi_{\tau h_1}^{k} : d_t e(u_{\tau h_1}^{k}) : d_t e(u_{\tau h_1}^{k})
\]

cf. (2.16). We then consider the minimization problem

\[
\text{minimize } c_\tau (\theta - \theta_{\tau h_1}^{k-1}, \theta - \theta_{\tau h_1}^{k-1}) + \tau \int_\Omega K \nabla \theta \cdot \nabla \theta - 2\xi_{\tau h_1}^{k} \theta \, dx + \tau (\alpha \theta, \theta)_{\Gamma, \tau h_2} - 2\tau \int_{\Gamma_1} f_{\tau h_1}^k \theta \, dS
\]

subject to \(\theta \in V_{\tau h_1}\).
Since (4.13) defines a convex optimization problem which involves a quadratic functional there exists a unique solution, denoted $\theta_{r_{h_{12}}}^k$, which solves (4.10).

Approximations provided by Algorithm ($\mathcal{A}$) obey the following discrete energy balance.

**Proposition 4.2. (Discrete energy balance.)** For iterates of Algorithm ($\mathcal{A}$) and every $K = 1, 2, \ldots, T/\tau$ we have

\begin{equation}
E_{\text{tot}}(u^K_{r_{h_{12}}}, \pi^K_{r_{h_{12}}}, \theta^K_{r_{h_{12}}}, d_t u^K_{r_{h_{12}}}) - E_{\text{tot}}(u^0_{r_{h_{12}}}, \pi^0_{r_{h_{12}}}, \theta^0_{r_{h_{12}}}, d_t u^0_{r_{h_{12}}})
\end{equation}

\begin{equation}
+ \frac{\tau^2}{2} \sum_{k=1}^{K} \int_{\Omega} |d^2_t u^K_{r_{h_{12}}}|^2 \, dx + \frac{\tau^2}{2} \sum_{k=1}^{K} \int_{\Omega} \left| d_t \mathcal{C}(e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) : (e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) \right|^2 \, dx
\end{equation}

\begin{equation}
= \tau \sum_{k=1}^{K} \mathcal{P}^{n}_{r_{h_{12}}}(d_t u^K_{r_{h_{12}}}, \sigma^{n}_{r_{h_{12}}}, \theta^{n}_{r_{h_{12}}}),
\end{equation}

where

\begin{equation}
\mathcal{P}^{n}_{r_{h_{12}}}(\dot{u}, \sigma, \theta) := \langle \sigma, d_t u^K_{\Omega - r_{h_{12}}} \rangle_{\Sigma} + \int_{\Gamma_1} g^k_{\tau} \cdot \dot{u} \, dS + \int_{\Gamma} f_{r_{h_{12}}} \, dS - (\alpha \theta, 1)_{r_{h_{12}}}
\end{equation}

and with $\sigma^{n}_{r_{h_{12}}}$ defined for every $v_{h_{1}} \in V_{r_{h_{1}}}$ through

\begin{equation}
\langle \sigma^{n}_{r_{h_{12}}}, v_{h_{1}} \rangle_{\Gamma_0} := \int_{\Omega} d^2_t u^K_{r_{h_{12}}} : v_{h_{1}} \, dx + \int_{\Omega} \mathcal{D} d_t u^K_{r_{h_{12}}} : v_{h_{1}} \, dx
\end{equation}

\begin{equation}
+ \int_{\Omega} \mathcal{C}(e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) : v_{h_{1}} \, dx - \int_{\Gamma_1} g^k_{\tau} \cdot v_{h_{1}} \, dS.
\end{equation}

**Proof.** We substitute $z := d_t (u^K_{r_{h_{12}}} - u^K_{D, r_{h_{12}}}) \in V_{r_{h_{1}}}$ into (4.7), test (4.8) by $d_t \pi^K_{r_{h_{12}}}$, and use the identity

\begin{equation}
\mathcal{C}(e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) : d_t (e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) = \frac{1}{2} d_t \Phi(u^K_{r_{h_{12}}}, \pi^K_{r_{h_{12}}}) + \frac{\tau}{2} d_t \mathcal{C}(e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) : (e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}})
\end{equation}

with $\Phi$ as in (2.8). We then add resulting identities, multiply by $\tau$, sum over $k = 1, 2, \ldots, K$, and employ discrete integration (or summation) by parts, i.e.,

\begin{equation}
\tau \sum_{k=1}^{K} d^2_t u^K_{r_{h_{12}}} : d_t u^K_{r_{h_{12}}} = \frac{1}{2} |d_t u^K_{r_{h_{12}}}|^2 - \frac{1}{2} |d_t u^0_{r_{h_{12}}}|^2 + \frac{\tau^2}{2} \sum_{k=1}^{K} |d^2_t u^K_{r_{h_{12}}}|^2,
\end{equation}

to deduce that

\begin{equation}
T_{\text{kin}}(d_t u^K_{r_{h_{12}}}) + \frac{1}{2} \Phi(u^K_{r_{h_{12}}}, \pi^K_{r_{h_{12}}}) + \frac{\tau}{2} \sum_{k=1}^{K} \int_{\Omega} \omega^K_{r_{h_{12}}} : d_t \pi^K_{r_{h_{12}}} \, dx
\end{equation}

\begin{equation}
+ \tau \sum_{k=1}^{K} \int_{\Omega} \mathcal{D} d_t e(u^K_{r_{h_{12}}}) : d_t e(u^K_{r_{h_{12}}}) \, dx + \tau \sum_{k=1}^{K} \int_{\Omega} \mathcal{D} d_t \pi^K_{r_{h_{12}}} : d_t \pi^K_{r_{h_{12}}} \, dx
\end{equation}

\begin{equation}
+ \frac{\tau^2}{2} \sum_{k=1}^{K} \int_{\Omega} |d^2_t u^K_{r_{h_{12}}}|^2 \, dx + \frac{\tau^2}{2} \sum_{k=1}^{K} \int_{\Omega} \mathcal{C}(e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) : (e(u^K_{r_{h_{12}}}) - \pi^K_{r_{h_{12}}}) \, dx
\end{equation}

\begin{equation}
= T_{\text{kin}}(d_t u^0_{r_{h_{12}}}) + \frac{1}{2} \Phi(u^0_{r_{h_{12}}}, \pi^0_{r_{h_{12}}}) + \frac{\tau}{2} \sum_{k=1}^{K} \int_{\Gamma} g^k_{\tau} \cdot d_t u^K_{r_{h_{12}}} \, dS + \sum_{k=1}^{K} \langle \sigma^{n}_{r_{h_{12}}}, d_t u^K_{D, r_{h_{12}}} \rangle_{\Gamma_0}.
\end{equation}

Choosing $z = 1$ in (4.10) to replace the third to fifth term on the left-hand side implies (4.14).
4.3. Passage to a semi-discrete scheme as $h_2 \to 0$. Given the sequence of approximations provided by Algorithm (a), we define piecewise constant approximations $\pi_{\tau h_1 h_2}$, $\varphi_{\tau h_1 h_2}$, $\vartheta_{\tau h_1 h_2}$, and $\xi_{\tau h_1 h_2}$ by
\begin{align}
(4.19) \quad & \pi_{\tau h_1 h_2}(t, \cdot) := \pi_{\tau h_1 h_2}^k(t, \cdot) := \pi_{\tau h_1 h_2}^k(t, \cdot) := \omega_{\tau h_1 h_2}^k(t, \cdot) := \theta_{\tau h_1 h_2}^k(t, \cdot) := \theta_{\tau h_1 h_2}^k(t, \cdot) := \xi_{\tau h_1 h_2}^k(t, \cdot), \\
(4.20) \quad & \varphi_{\tau h_1 h_2}(t, \cdot) := \varphi_{\tau h_1 h_2}^k(t, \cdot) := \varphi_{\tau h_1 h_2}^k(t, \cdot) := \vartheta_{\tau h_1 h_2}^{k-1}(t, \cdot) := \xi_{\tau h_1 h_2}^{k-1}(t, \cdot),
\end{align}
with $\xi_{\tau h_1 h_2}^k$ as in (4.12), as well as piecewise affine interpolants $u_{\tau h_1 h_2}$, $\pi_{\tau h_1 h_2}$, and $\theta_{\tau h_1 h_2}$ by
\begin{align}
\begin{split}
(4.21) \quad & u_{\tau h_1 h_2}(t, \cdot) := u_{\tau h_1 h_2}^k(t, \cdot) + (t - t_{k-1}) d_t u_{\tau h_1 h_2}^k, \\
& \pi_{\tau h_1 h_2}(t, \cdot) := \pi_{\tau h_1 h_2}^{k-1}(t, \cdot) + (t - t_{k-1}) d_t \pi_{\tau h_1 h_2}^k, \\
& \theta_{\tau h_1 h_2}(t, \cdot) := \theta_{\tau h_1 h_2}^{k-1}(t, \cdot) + (t - t_{k-1}) d_t \theta_{\tau h_1 h_2}^k,
\end{split}
\end{align}
for $t_{k-1} < t \leq t_k$, $k = 1, \ldots, T/\tau$.

We denote by $W^{1,2}(\Omega)_{\text{LCS}}$ the Hausdorff locally convex space consisting of $W^{1,2}(\Omega)^*$ equipped by the topology induced by countable collection of seminorms $| \cdot |_{h_2}$ induced by test with the countable collection of finite-dimensional spaces $V_{h_2}$, i.e. $|\xi|_{h_2} = \sup \|\xi\|_{W^{1,2}(\Omega)}$.

**Proposition 4.3. (First a-priori estimates.)** For all $\tau, h_1, h_2, h_2^* > 0$ with $h_2 \leq h_2^*$ we have $\theta_{\tau h_1 h_2} \geq 0$ almost everywhere in $Q$ and
\begin{align}
(4.22a) \quad & \|u_{\tau h_1 h_2}\|_{W^{1,2}(Q; W^{1,2}(\Omega; R^d))} \leq C, \\
(4.22b) \quad & \|\pi_{\tau h_1 h_2}\|_{W^{1,2}(Q; W^{1,2}(\Omega; R^d))} \leq C, \\
(4.22c) \quad & \|\varphi_{\tau h_1 h_2}\|_{L^2(Q; R^{d \times d})} \leq C, \\
(4.22d) \quad & \|\theta_{\tau h_1 h_2}\|_{L^\infty(Q; L^1(\Omega))} \leq C, \\
(4.22e) \quad & \|\theta_{\tau h_1 h_2}\|_{L^2(Q; W^{1,2}(\Omega))} \leq C_{h_1}, \\
(4.22f) \quad & \int_0^T \left( \frac{\|\theta_{\tau h_1 h_2}\|}{h_2^*} \right)^2 dt \leq C_{h_1}.
\end{align}

**Proof.** We argue as in the proof of Proposition 4.2 and notice that in the last identity we have
\begin{align}
(4.23) \quad & \omega_{\tau h_1 h_2}^k : d_t \pi_{\tau h_1 h_2}^k \geq 0.
\end{align}

To bound the terms on the right-hand side of the last identity in the proof of Proposition 4.2 we use
\begin{align}
(4.24) \quad & \tau \sum_{k=1}^K d_t^2 u_{\tau h_1 h_2}^k \cdot d_t u_{\tau h_1 h_2}^k = d_t u_{\tau h_1 h_2}^k \cdot d_t u_{\tau h_1 h_2}^k - \tau \sum_{k=1}^K d_t u_{\tau h_1 h_2}^{k-1} \cdot d_t^2 u_{\tau h_1 h_2}^k
\end{align}
and owing to assumption (3.5h) and the definition (4.6) we have that $\tau \|d_t^2 u_{\tau h_1 h_2}^k\|_{L^2(\Omega; R^d)}$ is summable over $k = 1, \ldots, T/\tau$ uniformly with respect to $\tau > 0$. We also use estimate
\begin{align}
(4.25) \quad & \int_{\Gamma_1} q_{\tau h_1 h_2}^k \cdot d_t u_{\tau h_1 h_2} dx \leq C_N \left\| q_{\tau h_1 h_2}^k \right\|_{L^{q/(q-1)}(\Gamma_1; R^d)} \left\| d_t u_{\tau h_1 h_2} \right\|_{W^{1,2}(\Omega; R^d)}
\end{align}
with $C_N$ denoting the norm of the trace operator $W^{1,2}(\Omega) \to L^q(\Gamma_1)$. After adding and subtracting $d_t u_{\tau h_1 h_2}^k$ and employing Korn's inequality we may use Young's inequalities to absorb terms in the left-hand side and deduce (4.22a,b). The estimate (4.22c) follows from (4.22a,b) via (4.8). By assumption on the triangulation $\mathcal{T}_{h_2}^2$ and employed numerical
integration we have $\theta_{r_1h_2}^k \geq 0$. Arguing as above to bound the right-hand side of (4.14) and using $(\alpha \theta_{r_1h_2}^k, 1)^{r_1h_2} \geq 0$ we then deduce (4.22d). Now, for $h_1 > 0$ fixed, all norms on $V_{0,h_1}$ and $V_{1,h_1}$ are equivalent, e.g., with the norm induced from $L^\infty(\Omega)$ and $W^{1,\infty}(\Omega)$, respectively, which shows that the piecewise constant interpolant $\overline{\xi}^r_{r_1h_2}$ of $\{\xi^k_{r_1h_2}\}_{k=1}^{T/r}$ (as defined in (4.12)) is uniformly bounded in $L^1(I; L^\infty(\Omega))$, hence also in $L^1(I; L^2(\Omega))$. Also $f_{h_1} \in L^2(I; L^2(\Gamma))$ and $\theta_{0,h_1} \in L^2(\Omega)$, which allows for usage of the standard $L^2$-theory for the heat equation to verify (4.22e,f).

In terms of the interpolated functions, we may write system (4.7)–(4.10) in the form

\begin{equation}
\int_\Omega \partial_t \left[ \frac{\partial u_{r_1h_2}}{\partial t} \right] z + D \frac{\partial c(u_{r_1h_2})}{\partial t} : e(z) + C(e(\overline{\pi}_{r_1h_2}) - \overline{\pi}_{r_1h_2}) : e(z) \, dx = \int_{\Gamma_1} \overline{\tau} \cdot z \, dS,
\end{equation}

\begin{equation}
\overline{w}_{r_1h_2} + \int_\Omega \frac{\partial \overline{\pi}_{r_1h_2}}{\partial t} \cdot e(\overline{\pi}_{r_1h_2}) - \overline{\pi}_{r_1h_2} = 0,
\end{equation}

\begin{equation}
\overline{w}_{r_1h_2} \in \partial \delta^* \left( S(\rho_{h_1} x_{r_1h_2}) \right) \left( \frac{\partial \overline{\pi}_{r_1h_2}}{\partial t} \right),
\end{equation}

\begin{equation}
\int_\Omega c_\epsilon \frac{\partial \theta_{r_1h_2}}{\partial t} w + \mathbb{K} \nabla \overline{\theta}_{r_1h_2} \cdot \nabla w - \overline{\xi}_{r_1h_2} w \, dx + \int_\Gamma \alpha \theta_{r_1h_2} w \, dS = \int_\Gamma \overline{f}_{r_1h_2} w \, dS + \overline{R}_{r_1h_2}(w),
\end{equation}

for every $(z, w) \in V_{1,h_1} \times V_{1,h_2}$ and where $[\cdot]$ denotes piece-wise affine interpolation in time.

Proposition 4.4. (Convergence for $h_2 \to 0$.) For fixed $\tau, h_1 > 0$ we have as $h_2 \to 0$, in terms of subsequences, $u_{r_1h_2} \to u_{r_1h_1}$ in $W^{1,2}(I; W^{1,2}(\Omega; \mathbb{R}^d))$, $\pi_{r_1h_2} \to \pi_{r_1h_1}$ in $W^{1,2}(I; L^2(\Omega; \mathbb{R}^d))$, $\overline{w}_{r_1h_2} \to \overline{w}_{r_1h_1}$ in $L^\infty(Q; \mathbb{R}^d)$, $\theta_{r_1h_2} \to \theta_{r_1h_1}$ in $L^2(I; W^{1,2}(\Omega))$, and $(u_{r_1h_1}, \pi_{r_1h_1}, \overline{w}_{r_1h_1}, \theta_{r_1h_1})$ solves (4.26)–(4.28) with $h_2$ omitted and

\begin{equation}
\int_Q \mathbb{K} \nabla \overline{\theta}_{r_1h_1} \cdot \nabla w - \overline{\xi}_{r_1h_1} w \, dx + c_\epsilon \overline{\theta}_{r_1h_1} \frac{\partial w}{\partial t} \, dt + \int_\Omega c_\epsilon \theta_{0,h_1}(x) w(0, x) \, dx = \int_\Gamma \overline{f}_{r_1h_1} w \, dS + \int_\Gamma \alpha \theta_{0,h_1}(x) w(0, x) \, dx
\end{equation}

for all $w \in C^\infty(\overline{Q})$ with $w(T, \cdot) = 0$ and with $\theta_{0,h_1} := \mathcal{J}^{+}_{1,h_1} \theta_0$ and

\begin{equation}
\overline{\xi}_{r_1h_1} = \overline{w}_{r_1h_1} : \frac{\partial \pi_{r_1h_1}}{\partial t} + \mathbb{B} \frac{\partial \pi_{r_1h_1}}{\partial t} : \frac{\partial \pi_{r_1h_1}}{\partial t} + D \frac{\partial e(u_{r_1h_1})}{\partial t} : e(u_{r_1h_1}).
\end{equation}

Proof. The selection of weakly convergent subsequences follows from the estimates (4.22a-e). By the Aubin-Lions theorem generalized for Hausdorff locally convex spaces as used in the estimate (4.22e), cf. [26, Lemma 7.7], we have $\theta_{r_1h_2} \to \theta_{r_1h_1}$ in $L^2(Q)$.

As $\tau$ and $h_1$ are fixed, the sequences $\{u_{r_1h_1}\}_{h_2>0}$, $\{\pi_{r_1h_2}\}_{h_2>0}$, and $\{\overline{w}_{r_1h_2}\}_{h_2>0}$ belong to finite-dimensional subspaces and thus, the subsequences converge in fact strongly, as claimed. Moreover, also the piecewise constant interpolant $\overline{\pi}_{r_1h_2}$ converges to $\overline{\pi}_{r_1h_1}$ which is indeed the piecewise constant interpolant related to $u_{r_1h_1}$, and similarly $\overline{\pi}_{r_1h_2} \to \overline{\pi}_{r_1h_1}$ and $\overline{w}_{r_1h_2} \to \overline{w}_{r_1h_1}$. The limit passage in (4.26) and (4.27) is then straightforward. As to (4.29), the only peculiarity is in the numerical integration contained in residual functional
$R_{\tau h_1h_2}$. For any $w \in C^\infty(Q)$ with $w(T) = 0$ and $w_h(t, \cdot) := \mathcal{I}_{h_2}w(t, \cdot) \in V_{1,h_2}$ we have

\begin{equation}
(4.32) \int_0^T \theta_{\tau h_1h_2}(w_{h_2}) \, dt = \int_0^T \int_\Omega \frac{\partial \theta_{\tau h_1h_2}}{\partial t} \, w_{h_2} \, dx - \left( \frac{\partial \theta_{\tau h_1h_2}}{\partial t}, w_{h_2} \right)_{h_2} \, dt \\
+ \int_0^T \left( \alpha \theta_{\tau h_1h_2}, w_{h_2} \right)_{h_2} - \int_\Gamma \alpha \theta_{\tau h_1h_2} \, w_{h_2} \, dS \, dt =: E_1 + E_2.
\end{equation}

For $E_1$ we verify, using by-part integration in time and (4.2),

\begin{equation}
(4.33) E_1 = - \int_0^T \int_\Omega \theta_{\tau h_1h_2} \frac{\partial w_{h_2}}{\partial t} \, dx - \left( \theta_{\tau h_1h_2}, \frac{\partial w_{h_2}}{\partial t} \right)_{h_2} \, dt \\
+ \int_\Omega \theta_{\tau h_1h_2}(0, \cdot) w_{h_2}(0, \cdot) \, dx - \left( \theta_{\tau h_1h_2}(0, \cdot), w_{h_2}(0, \cdot) \right)_{h_2} \\
\leq C_0 h_2 \left( \| \theta_{\tau h_1h_2} \|_{L^2(I; W^{1,2}(\Omega))} \left\| \frac{\partial w_{h_2}}{\partial t} \right\|_{L^2(I; L^2(\Omega))} + \| \theta_{\tau h_1h_2}(0, \cdot) \|_{L^2(\Omega)} \| w_{h_2}(0, \cdot) \|_{W^{1,2}(\Omega)} \right).
\end{equation}

Notice that $\theta_{\tau h_1h_2}(0, \cdot) = \mathcal{I}_{h_2} \theta_{0,h_1}$ and since $\theta_{0,h_1} \in V_{1,h_1}$ we have $\theta_{\tau h_1h_2}(0, \cdot) \to \theta_{0,h_1}$ in $L^2(\Omega)$ as $h_2 \to 0$. Employing (4.2) and a nodal interpolation estimate we verify for $E_2$ that

\begin{equation}
(4.34) E_2 = \int_0^T \left( \mathcal{I}_{h_2} [\tilde{\alpha} \theta_{\tau h_1h_2}], w_{h_2} \right)_{h_2} - \left( \mathcal{I}_{h_2} [\tilde{\alpha} \theta_{\tau h_1h_2}], w_{h_2} \right)_{h_2} \, dS \, dt \\
+ \int_0^T \left( \mathcal{I}_{h_2} [\tilde{\alpha} \theta_{\tau h_1h_2}] - \tilde{\alpha} \theta_{\tau h_1h_2} \right) w_{h_2} \, dS \, dt \\
\leq C_0 h_2 \left\| \tilde{\alpha} \theta_{\tau h_1h_2} \right\|_{L^2(I; W^{1,2}(\Omega))} \| w_{h_2} \|_{L^2(I; L^2(\Omega))} \to 0,
\end{equation}

where $\tilde{\alpha}$ is an extension of $\alpha$ qualified in (3.5e). It is a routine calculation to show that this qualification allows for $\tilde{\alpha} \in W^{1,d+\varepsilon}(\Omega) \subset W^{1,d}(\Omega) \cap L^\infty(\Omega)$ which just guarantees that $\theta \mapsto \tilde{\alpha} \theta$ is a bounded operator $W^{1,2}(\Omega) \to W^{1,2}(\Omega)$. On combining the estimates we deduce that the left-hand side of (4.32) tends to zero as $h_2 \to 0$.

As to (4.28), we first realize that $\tilde{\theta}_{\tau h_1h_2} \to \tilde{\theta}_{\tau h_1}^R$ in $L^2(Q)$ as $h_2 \to 0$ with $\tilde{\theta}_{\tau h_1}^R$ piecewise constant in time. Taking $w, z \in V_{0,h_1}$ such that $w \in \partial \delta^*_{S(P_{0,h_1}\tilde{\theta}_{\tau h_1}^R(t, \cdot))}(z)$, we need to pass for almost every $t \in I$ to the limit in

\begin{equation}
(4.35) \int_\Omega \left( \tilde{\theta}_{\tau h_1h_2}(t, \cdot) - w_{h_2} \right) \cdot \frac{\partial \pi_{\tau h_1h_2}}{\partial t} (t, \cdot) - z \, dx \geq 0
\end{equation}

for suitable $w_{h_2} \in V_{0,h_2}$ satisfying $w_{h_2} \in \partial \delta^*_{S(P_{0,h_1}\tilde{\theta}_{\tau h_1}^R(t, \cdot))}(z)$. As in (3.6), we employ

\begin{equation}
(4.36) w_{h_2} = \mathcal{Y}(P_{0,h_1}\tilde{\theta}_{\tau h_1h_2}(t, \cdot))w / \mathcal{Y}(P_{0,h_1}\tilde{\theta}_{\tau h_1}^R(t, \cdot)).
\end{equation}

Since $\tilde{\theta}_{\tau h_1h_2}(t, \cdot) \to \tilde{\theta}_{\tau h_1}^R(t, \cdot)$ in $L^2(\Omega)$, we have also $P_{0,h_1}\tilde{\theta}_{\tau h_1h_2}(t, \cdot) \to P_{0,h_1}\tilde{\theta}_{\tau h_1}^R(t, \cdot)$ in $L^p(\Omega)$ and, owing to dominated convergence theorem, $\mathcal{Y}(P_{0,h_1}\tilde{\theta}_{\tau h_1h_2}) \to \mathcal{Y}(P_{0,h_1}\tilde{\theta}_{\tau h_1}^R)$ in any $L^p(Q)$ with $p < \infty$. Therefore, we have $w_{h_2} \to w$ in $L^p(Q; \mathbb{R}^{d \times d})$ even for any $p < \infty$. Recalling the strong convergence of $\{\tilde{\theta}_{\tau h_1h_2} \}_{h_2 > 0}$ and $\{\frac{\partial \pi_{\tau h_1h_2}}{\partial t} \}_{h_2 > 0}$ in the finite-dimensional subspaces the limit passage in (4.35) is straightforward. \[\square\]

4.4. Passage to the very weak formulation. Having passed to the semi-discrete scheme (4.26)–(4.28) (with $h_2$ omitted) and (4.30) we may employ various nonlinearities of $\theta_{\tau h_1}$ as test functions in (4.30). This allows to derive bounds for $\nabla \theta_{\tau h_1}$ that are uniform in $\tau, h_1$ which would not have been available in the fully discrete heat equation.
Proposition 4.5. (Further a-priori estimates.) For all $\tau, h_1 > 0$ and $0 < \delta \leq \frac{1}{d+1}$ we have

\begin{align}
(4.37a) \quad & \left\| \nabla \theta_{\tau h_1} \right\|_{L^{\frac{d+2}{d+1}}(Q;\mathbb{R}^d)} \leq C_\delta, \\
(4.37b) \quad & \left\| \frac{\partial \theta_{\tau h_1}}{\partial t} \right\|_{L^1(I;W^{-1-\delta/2,2}(\Omega))} \leq C.
\end{align}

Comments to the proof. The estimate (4.37a) can be obtained from (4.22d) for any “semi-discrete-in-time” solution to (4.30) with the technique developed by Boccardo, Gallouët et al. [4, 5], see also [28]. The technique uses tests of the heat equation by $\varphi(\theta_{\tau h_1})$ with various bounded nondecreasing Lipschitz-continuous nonlinearities $\varphi : \mathbb{R} \rightarrow \mathbb{R}$, and then employs Hölder inequalities and Gagliardo-Nirenberg interpolation with (4.22d). For the time-discrete case, it is important that $\varphi$ is nondecreasing and bounded, hence its potential, denoted by $\tilde{\varphi}$, is convex and has at most linear growth. Therefore, we have

\begin{equation}
(4.38) \quad (d_t \theta^k_{\tau h_1}) \varphi(\theta^k_{\tau h_1}) \geq d_t \tilde{\varphi}(\theta^k_{\tau h_1}),
\end{equation}

which, after summation over $k = 1, ..., T/\tau$ and integration over $\Omega$ is bounded since $\tilde{\varphi}(\theta^k_{\tau h_1}) \in L^1(\Omega)$. Thus, the estimation reduces to the spatial gradient term which is done exactly in the same way as in the time-continuous case in [4, 5].

Finally, the estimate (4.37b) follows from (4.22d) with $h_2$ omitted and (4.37a) by testing (4.30) with functions $w \in L^\infty(I;W^{1+d/2,2}_{0}(\Omega))$ which have essentially bounded gradients. □

Proposition 4.6. (Convergence for $(\tau, h_1) \rightarrow (0, 0)$.) As $(\tau, h_1) \rightarrow (0, 0)$, in terms of subsequence, we have $u_{\tau h_1} \rightharpoonup u$ in $W^{1,2}(I;W^{1,2}(\Omega;\mathbb{R}^d))$, $\pi_{\tau h_1} \rightharpoonup \pi$ in $W^{1,2}(I;L^2(\Omega;\mathbb{R}^{d\times d}))$, $\omega_{\tau h_1} \rightharpoonup \omega$ in $L^2(I;\mathbb{R}^d)$,

\begin{equation}
\theta_{\tau h_1} \rightharpoonup \theta \quad \text{in} \quad L^{\frac{d+2}{d+1}}(Q \cap L^\infty(I;L^1(\Omega)))
\end{equation}

with any $0 < \delta \leq \frac{1}{d+1}$, and $(u, \pi, \omega, \theta)$ is a very weak solution of (2.2) and (3.1)–(3.2) in the sense of Definition 3.1.

Proof. The selection of weakly convergent subsequences follows by the standard Banach selection principle from the estimates (4.22a-d) which are inherited also for the approximate solution $(u_{\tau h_1}, \pi_{\tau h_1}, \omega_{\tau h_1}, \theta_{\tau h_1})$, and by the estimates (4.37) and

\begin{equation}
(4.40a) \quad \int_0^T \left\| \frac{\partial u_{\tau h_1}}{\partial t} \right\|^2_{L^1(\gamma_{0,h^*_1})} dt \leq C \quad \text{for any } h_1 \leq h^*_1,
\end{equation}

where the seminorm $\left\| \cdot \right\|_{\gamma_{0,h^*_1}}$ is defined as

\begin{equation}
(4.41) \quad |\xi|_{\gamma_{0,h^*_1}} := \sup_{||v||_{L^{2}((0,T) \times (\mathbb{R}^d, \mathbb{R}^d))} \leq 1} \int_Q |\xi \cdot v| dx dt.
\end{equation}

The estimate (4.40) can be obtained by testing (4.26), limited by $h_2 \rightarrow 0$, by test functions from $L^2(I;V^d_{0,h^*_1})$. Using (4.37b), arguing with the Aubin-Lions theorem, and interpolating with the estimate (4.22d) for $\theta_{\tau h_1}$, cf. [26, Lemmas 7.7 and 7.8], we have also $\theta_{\tau h_1} \rightarrow \theta$ in $L^{\frac{d+2}{d+1}-\delta}(Q)$, $0 < \varepsilon \leq 2/d$.

We want to prove that $\omega \in \partial \delta^e_{S(\theta)}(\frac{\partial \omega}{\partial \pi})$. As in the proof of Proposition 4.4, we consider $w, z \in L^2(Q;\mathbb{R}^{d\times d})$ such that $w \in \partial \delta^e_{S(\theta)}(z)$ almost everywhere in $Q$. We know that $\omega_{\tau h_1} \in
\[ \partial \delta^*_{S(P_{0,h_1}^{\pi_{\tau h_1}})} (\frac{\partial}{\partial t} \pi_{\tau h_1}) \text{, and, owing to the maximal monotonicity of } \partial \delta^*_{S(\theta)} (\cdot) : \mathbb{R}^{d \times d} \to \mathbb{R}^{d \times d}, \]

it suffices to pass to the limit in the inequality

\[ (4.42) \quad \int_Q (\bar{w}_{\tau h_1} - w_{\tau h_1}) : \left( \frac{\partial \pi_{\tau h_1}}{\partial t} - z \right) \, dx \, dt \geq 0 \]

for suitable \( w_{\tau h_1} \in \partial \delta^*_{S(P_{0,h_1}^{\pi_{\tau h_1}})} (z) \). Like in (3.6), we take \( w_{\tau h_1} = \mathcal{Y}(P_{0,h_1}^{\pi_{\tau h_1}}) w / \mathcal{Y}(\theta) \) which satisfies \( w_{\tau h_1} \to w \) in \( L^q(Q; \mathbb{R}^{d \times d}) \) for every \( 1 \leq q < \infty \) and \( w_{\tau h_1} \in \partial \delta^*_{S(P_{0,h_1}^{\pi_{\tau h_1}})} (z) \) almost everywhere in \( Q \). Following [9] (see also [26, Prop. 11.5]), the critical limit passage of the product \( \bar{w}_{\tau h_1} : \frac{\partial \pi_{\tau h_1}}{\partial t} \) can be performed by using the information from the equations themselves. Namely, we use (4.27) (with \( h_2 \) omitted) tested by \( \frac{\partial}{\partial t} \pi_{\tau h_1} \) and add (4.26) (with \( h_2 \) omitted) tested by \( \frac{\partial}{\partial t} (u_{\tau h_1} - u_{D,h_1}) \), and estimate the limit superior as follows:

\[ (4.43) \quad \lim \sup_{(\tau, h_1) \to (0,0)} \int_Q \bar{w}_{\tau h_1} : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx \, dt \]

\[ = \lim \sup_{(\tau, h_1) \to (0,0)} \int_Q \mathbb{C} (e(\bar{u}_{\tau h_1}) - \pi_{\tau h_1}) : \frac{\partial \pi_{\tau h_1}}{\partial t} - \mathbb{B} \frac{\partial \pi_{\tau h_1}}{\partial t} : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx \, dt \]

\[ = \lim \sup_{(\tau, h_1) \to (0,0)} \left( \int_Q - \mathbb{C} (e(\bar{u}_{\tau h_1}) - \pi_{\tau h_1}) : e \left( \frac{\partial u_{\tau h_1}}{\partial t} \right) \, dx \, dt + \int_{\Sigma_0} \sigma_{\tau h_1} \cdot \frac{\partial u_{D,h_1}}{\partial t} \, dS \, dt + \int_{\Sigma_1} \mathcal{Y}_\tau : \frac{\partial u_{\tau h_1}}{\partial t} \, dS \, dt \right) \]

\[ \leq \lim_{h_1 \to 0} \int_{\Omega} \frac{1}{2} \mathbb{C} (e(u_{0,h_1}(x)) - \pi_{0,h_1}(x)) : (e(u_{0,h_1}(x)) - \pi_{0,h_1}(x)) + \frac{\theta}{2} \left| \bar{u}_{0,h_1}(x) \right|^2 \, dx \]

\[ - \lim \inf_{(\tau, h_1) \to (0,0)} \left( \int_{\Omega} \frac{1}{2} \mathbb{C} (e(u_{\tau h_1}(T,x)) - \pi_{\tau h_1}(T,x)) : (e(u_{\tau h_1}(T,x)) - \pi_{\tau h_1}(T,x)) \right) \]

\[ + \frac{\theta}{2} \left| \frac{\partial u_{\tau h_1}}{\partial t}(T,x) \right|^2 \, dx + \int_Q \mathbb{B} \frac{\partial \pi_{\tau h_1}}{\partial t} : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx + \mathbb{D} e \left( \frac{\partial u_{\tau h_1}}{\partial t} \right) : e \left( \frac{\partial u_{\tau h_1}}{\partial t} \right) \, dx \, dt \]

\[ + \lim_{(\tau, h_1) \to (0,0)} \left( \int_{\Sigma_0} \sigma_{\tau h_1} \cdot \frac{\partial u_{D,h_1}}{\partial t} \, dS \, dt + \int_{\Sigma_1} \mathcal{Y}_\tau \cdot \frac{\partial u_{\tau h_1}}{\partial t} \, dS \, dt \right). \]

The first inequality in (4.43) is due to a numerical time-integration error, cf. the last identity in the proof of Proposition 4.2. Since initial and boundary data converge strongly and since \( u_{\tau h_1}(T, \cdot) \to u(T, \cdot) \) in \( W^{1,2}(\Omega; \mathbb{R}^d) \) and \( \pi_{\tau h_1}(T, \cdot) \to \pi(T, \cdot) \) in \( L^2(\Omega; \mathbb{R}^{d \times d}) \) by the a-priori estimates (4.22a,b) we may argue with weakly lower semi-continuity to verify that

\[ (4.44) \quad \lim \sup_{(\tau, h_1) \to (0,0)} \int_Q \bar{w}_{\tau h_1} : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx \, dt \]

\[ \leq \int_{\Omega} \frac{1}{2} \mathbb{C} (e(u_0(x)) - \pi_0(x)) : (e(u_0(x)) - \pi_0(x)) + \frac{\theta}{2} \left| \bar{u}_0(x) \right|^2 \, dx \]

\[ - \int_{\Omega} \frac{1}{2} \mathbb{C} (e(u(T,x)) - \pi(T,x)) : (e(u(T,x)) - \pi(T,x)) + \frac{\theta}{2} \left| \frac{\partial u}{\partial t}(T,x) \right|^2 \, dx \]

\[ - \int_{\Omega} \mathbb{B} \frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} + \mathbb{D} e \left( \frac{\partial u}{\partial t} \right) : e \left( \frac{\partial u}{\partial t} \right) \, dx \, dt + \int_{\Omega} \left\langle \sigma, \frac{\partial u_D}{\partial t} \right\rangle_{\Gamma_0} \, dt + \int_{\Sigma_1} \mathcal{Y}_\tau \cdot \frac{\partial u}{\partial t} \, dS \, dt. \]
By the above convergence properties of the approximations we may employ (2.2) and (3.1a), which are obtained in the limit from (4.26) and (4.27) (with \( h_2 \) omitted) as \((\tau, h_1) \to (0,0)\), to conclude

\[
\limsup_{(\tau, h_1) \to (0,0)} \int_Q \omega_{\tau h_1} : \frac{\partial \sigma_{\tau h_1}}{\partial t} \, dx \, dt
\]

\[
\leq -\int_0^T \int_Q \left\langle g \frac{\partial^2 u}{\partial t^2} - \frac{\partial u}{\partial t} \frac{\partial u}{\partial t} \right\rangle \, dt + \int_Q \mathcal{C}(e(u)) : e\left( \frac{\partial u}{\partial t} \right) + \mathbb{B} e\left( \frac{\partial u}{\partial t} \right) : e\left( \frac{\partial u}{\partial t} \right) \, dx \, dt
\]

\[
+ \int_0^T \int_Q \sigma : \frac{\partial u}{\partial t} \, dt + \int_0^T \int_Q g \cdot \frac{\partial u}{\partial t} \, dx \, dt + \int_Q \mathcal{C}(e(u)) : \frac{\partial \pi}{\partial t} - \mathbb{B} \frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \, dx \, dt
\]

\[
= \int_Q \omega : \frac{\partial \pi}{\partial t} \, dx \, dt,
\]

where \( \sigma_{\tau h_1} \) is the approximate normal stress on \( \Sigma_0 \) defined, like in (2.13), by

\[
\int_{\Sigma_0} \sigma_{\tau h_1} : \nu \, dS \, d\tau = \int_Q \varphi \left( \frac{\partial u_{\tau h_1}}{\partial t} \right) \frac{\partial u_{\tau h_1}}{\partial t} \, dx \, dt + \mathcal{C}(e(\pi_{\tau h_1} - \pi_{\tau h_1})) : e(\pi) \, dx \, dt
\]

\[
- \int_{\Sigma_1} \pi_{\tau h_1}(t, \cdot) : \nu \, dS \, d\tau
\]

where \( \pi \in V^d_{1, h_1} \) is (any) extension of \( \nu \), and \( \sigma \) and \( \langle \sigma, \cdot \rangle_{\Gamma_0} \) is as in (2.13).

Eventually, we estimate the limit superior in (4.42) to verify that \( \omega \in \partial \delta_{S_{\theta}}^{\ast}(\frac{\partial \pi}{\partial t}) \).

Limit passage in the heat equation requires still the (at least weak) convergence of the dissipation heat \( \xi_{\tau h_1} \to \xi \) in \( L^1(Q) \) with \( \xi \) satisfying (2.16). We know that \( \{ \delta_{S_{\theta}}^{\ast}(P_{0, h_1} \pi_{\tau h_1}) \}_{\tau h_1 > 0} \) is bounded in \( L^2(Q) \), hence as a subsequence it must converge to some \( \xi_1 \) weakly in \( L^2(Q) \). As \( P_{0, h_1} \pi_{\tau h_1} \to \theta \) in \( L^{\frac{d+2-\epsilon}{2}}(Q) \) with \( \epsilon > 0 \) and the integrand \( \langle \vartheta, \pi \rangle \to \delta_{S_{\theta}}^{\ast}(\pi) \) is continuous in both variables and convex in \( \pi \)-variable, we have by (norm×weak)-lower semicontinuity argument (cf. also [22, Lemma 5.1]), we have \( \xi_1 \geq \delta_{S_{\theta}}^{\ast}(\pi) \). In fact, in our special case (3.5d), we have simply \( \delta_{S_{\theta}}^{\ast}(\pi) = \Upsilon(\vartheta) \delta_{S_{\theta}}^{\ast}(\pi) \).

Also \( \{ \mathbb{B} e(\frac{\partial u_{\tau h_1}}{\partial t}) \}_{\tau h_1 > 0} \) and \( \{ \mathbb{B} \frac{\partial \pi_{\tau h_1}}{\partial t} : \frac{\partial \pi_{\tau h_1}}{\partial t} \}_{\tau h_1 > 0} \) are bounded in \( L^1(Q) \), hence as subsequences they must converge weakly* in measures on \( \overline{Q} \) to some \( \xi_2 \) and \( \xi_3 \), respectively. By weak* lower semicontinuity, again \( \xi_2 \geq \mathbb{D} e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) \) and \( \xi_3 \geq \mathbb{B} \frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \).

Arguing as in (4.43)-(4.45), we have

\[
\int_Q \delta_{S_{\theta}}^{\ast}(\frac{\partial \pi}{\partial t}) + \mathbb{B} e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) + \mathbb{D} e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) \, dx \, dt
\]

\[
\leq \int_Q \xi_1(\tau h_1) \, dx \, dt + \int_Q \xi_2(\tau h_1) \, dx \, dt + \int_Q \xi_3(\tau h_1) \, dx \, dt
\]

\[
\leq \liminf_{(\tau, h_1) \to (0,0)} \int_Q \xi_{\tau h_1} \, dx \, dt \leq \limsup_{(\tau, h_1) \to (0,0)} \int_Q \xi_{\tau h_1} \, dx \, dt
\]
and

\[
(4.48) \quad \int_Q \delta_{S(\theta)}^{\ast}(\frac{\partial \pi}{\partial t}) + \mathbb{D}e(\frac{\partial u}{\partial t} : e(\frac{\partial u}{\partial t})) + \mathbb{B}\frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \, dx \, dt \\
\leq \limsup_{(\tau, h_1) \to (0, 0)} \left( \int_Q -C(e(\bar{u}_{\tau h_1}) - \bar{\pi}_{\tau h_1}) : e(\frac{\partial u_{\tau h_1}}{\partial t}) - \varrho \frac{\partial}{\partial t} \left[ \frac{\partial u_{\tau h_1}}{\partial t} \right] \frac{\partial u_{\tau h_1}}{\partial t} \, dx \, dt \\
+ \int_{\Sigma_0} \sigma_{\tau h_1} : \frac{\partial u_{\tau h_1}}{\partial t} \, dS \, dt \right) \leq \int_Q \mathbb{C}(e(\bar{u}_{\tau h_1}) - \bar{\pi}_{\tau h_1}) : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx \, dt
\]

\[
+ \int_{\Sigma_1} \mathbb{C}(e(\bar{u}_{\tau h_1}) - \bar{\pi}_{\tau h_1}) : \frac{\partial \pi_{\tau h_1}}{\partial t} \, dx \, dt
\]

\[
\leq -\int_0^T \left( \theta \frac{\partial^2 u}{\partial t^2} + \frac{\partial u}{\partial t} \right) \, dt - \int_Q \mathbb{C}(e(u) - \pi) : e(\frac{\partial u}{\partial t}) \, dx \, dt \\
+ \int_0^T \left( \varphi, \frac{\partial \mathcal{D}}{\partial t} \right) \, dt + \int_{\Sigma_1} g \cdot \frac{\partial u}{\partial t} \, dS \, dt + \int_Q \mathbb{C}(e(u) - \pi) : \frac{\partial \pi}{\partial t} \, dx \, dt
\]

\[
= \int_Q \delta_{S(\theta)}^{\ast}(\frac{\partial \pi}{\partial t}) + \mathbb{D}e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) + \mathbb{B}\frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \, dx \, dt.
\]

The last equality follows by testing the limit equations (2.2) and (2.3) by \( \frac{\partial (u-u_{\text{ID}})}{\partial t} \) and by \( \frac{\partial \pi}{\partial t} \), respectively, and by using also (3.3) and the fact that \( \frac{\partial^2 u}{\partial t^2} \) is in duality with \( \frac{\partial u}{\partial t} \). Therefore, all inequalities in (4.48) are, in fact, equalities and

\[
(4.49) \quad \lim_{(\tau, h_1) \to (0, 0)} \int_Q \xi_{\tau h_1} \, dx \, dt = \int_Q \delta_{S(\theta)}^{\ast}(\frac{\partial \pi}{\partial t}) + \mathbb{D}e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) + \mathbb{B}\frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \, dx \, dt.
\]

Hence \( \xi_{\tau h_1} \) converges to \( \delta_{S(\theta)}^{\ast}(\frac{\partial \pi}{\partial t}) + \mathbb{D}e(\frac{\partial u}{\partial t}) : e(\frac{\partial u}{\partial t}) + \mathbb{B}\frac{\partial \pi}{\partial t} : \frac{\partial \pi}{\partial t} \) weakly* in measures on \( Q \), and because of the absolute continuity of the limit, even weakly in \( L^1(Q) \). Then the limit passage in the discrete heat equation is straightforward.

\[ \blacksquare \]

**Corollary 4.7.** Under the data qualification (3.5) a very weak solution in the sense of Definition 3.1 exists.

5. **Implementation of the algorithm and illustrative simulations**

In our implementation we solved the variational inclusion exactly, making use of the equivalence

\[
(5.1) \quad \omega_{\tau h_1}^k \in \partial \mathcal{S}(\theta_{\tau h_1}^{k-1})(d_t \pi_{\tau h_1}^k) \iff d_t \pi_{\tau h_1}^k \in \partial \mathcal{S}(\theta_{\tau h_1}^{k-1})(\omega_{\tau h_1}^k).
\]

We make the simplification \( \mathbb{B} = 0 \) and introduce \( A_{\tau h_1}^k := d_t e(u_{\tau h_1}^k) - \tau^{-1} \mathcal{C}^{-1} \omega_{\tau h_1}^{k-1} \).

Noting the identity \( \pi_{\tau h_1}^k = e(u_{\tau h_1}^k) - \mathcal{C}^{-1} \omega_{\tau h_1}^k \), the flow rule then reads

\[
(5.2) \quad A_{\tau h_1}^k - \tau^{-1} \mathcal{C}^{-1} \omega_{\tau h_1}^k \in \partial \mathcal{S}(\theta_{\tau h_1}^{k-1})(\omega_{\tau h_1}^k).
\]

For certain material laws and stress-strain relations it is possible to derive an explicit formula for the unique solution \( \omega_{\tau h_1}^k \) of (5.2) in terms of (given) \( A_{\tau h_1}^k, \theta_{\tau h_1}^{k-1}, \) and \( \tau \).

We confine ourselves to the linear stress-strain relation

\[
(5.3) \quad \omega_{\tau h_1}^k = \mathcal{C} \varepsilon_{\tau h_1}^k = \lambda \text{tr} \varepsilon_{\tau h_1}^k \mathbf{I}_{d \times d} + 2 \mu \varepsilon_{\tau h_1}^k
\]

for Lamé coefficients \( \lambda \geq 0 \) and \( \mu > 0 \) and the elastic strain tensor \( \varepsilon_{\tau h_1}^k = e(u_{\tau h_1}^k) - \pi_{\tau h_1}^k \). Moreover, we consider perfect plasticity defined through the von-Mises yield function \( \Phi(\omega) := |\text{dev} \omega| - \omega_y,0 \) and the corresponding set of admissible elastic stresses

\[
(5.4) \quad S_0 := \{ \omega \in \mathbb{P}_{\text{sym}}^d : |\text{dev} \omega| \leq \omega_y,0 \},
\]
where $\omega_{y,0}$ is the yield stress and “dev” denotes the trace free part of a tensor. Temperature dependence is included through the bounded, continuous function $\Upsilon : \mathbb{R}^+ \rightarrow \mathbb{R}^+$ which describes a decrease of the yield stress for large temperatures; we have

$$S(\theta) = \Upsilon(\theta)S_0 = \{ \omega \in \mathbb{R}^{d \times d}_{\text{sym}} : |\text{dev } \omega| \leq \omega_{y,0}\Upsilon(\theta) \}.$$ 

With these definitions we are in the setting of [7, Theorem 3.1] and may deduce that for given $A_{\tau h_1 h_2}^k, \theta_{\tau h_1 h_2}^{k-1}$, and $\tau > 0$ there exists a unique solution $\omega_{\tau h_1 h_2}^k$ of (5.2) which is given by

$$\omega_{\tau h_1 h_2}^k = \Sigma(A_{\tau h_1 h_2}^k, P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1}, \tau) := (\lambda + 2\mu/d) \text{tr} \tau A_{\tau h_1 h_2}^k I_{d \times d} + F(A_{\tau h_1 h_2}^k, P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1}, \tau) \text{dev } \tau A_{\tau h_1 h_2}^k$$

where

$$F(A_{\tau h_1 h_2}^k, \theta_{\tau h_1 h_2}^{k-1}, \tau) = \left\{ \begin{array}{ll} \frac{\omega_{y,0}\Upsilon(P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1})}{|\text{dev } \tau A_{\tau h_1 h_2}^k|} & \text{for } |\text{dev } \tau A_{\tau h_1 h_2}^k| \geq \frac{\omega_{y,0}\Upsilon(P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1})}{2\mu}, \\ 2\mu & \text{for } |\text{dev } \tau A_{\tau h_1 h_2}^k| \leq \frac{\omega_{y,0}\Upsilon(P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1})}{2\mu}. \end{array} \right.$$ 

In particular, the plastic phase occurs for $|\text{dev } \tau A_{\tau h_1 h_2}^k| \geq \omega_{y,0}\Upsilon(P_{0, h_1} \theta_{\tau h_1 h_2}^{k-1})/(2\mu)$. For explicit formulas in case of other plastic material behavior such as plasticity with isotropic hardening we refer the reader to [7].

In addition to the simplification $B = 0$ we set $\rho := 0$ and $D := 0$ in the numerical experiments reported below. The discrete scheme (4.7)-(4.10) then reduces to the following quasi-stationary, pure (nonlinear) displacement and temperature formulation: Given $(u_{\tau h_1 h_2}^{k-1}, \pi_{\tau h_1 h_2}^{k-1}, \omega_{\tau h_1 h_2}^{k-1}, \theta_{\tau h_1 h_2}^{k-1}) \in V_{1,h_1}^d \times V_{0,h_1}^{d\times d} \times V_{0,h_1}^{d\times d} \times V_{1,h_2}$ find $u_{\tau h_1 h_2}^k \in V_{1,h_1}^d$ such that

$$u_{\tau h_1 h_2}^k|_{\Gamma_0} = u_{D, \tau h_1} \text{ and }$$

$$\int_{\Omega} \Sigma(A_{\tau h_1 h_2}^k u_{\tau h_1 h_2}^k, \theta_{\tau h_1 h_2}^{k-1}, \tau) : e(z) \, dx = \int_{\Gamma_1} g^k \cdot z \, dS$$

for all $z \in V_{1,h_1}^d$ with $z|_{\Gamma_0} = 0$. Subsequently, set $\omega_{\tau h_1 h_2}^k := \Sigma(A_{\tau h_1 h_2}^k, \theta_{\tau h_1 h_2}^{k-1}, \tau)$ and $\pi_{\tau h_1 h_2}^k := e(u_{\tau h_1 h_2}^k) - \text{dev } \omega_{\tau h_1 h_2}^k$ and compute $\theta_{\tau h_1 h_2}^k \in V_{1,h_2}$ such that

$$c_v(d_t \theta_{\tau h_1 h_2}^k, z) + \int_{\Omega} \nabla \theta_{\tau h_1 h_2}^k \nabla z \, dx + (\alpha \theta_{\tau h_1 h_2}^k, z)_{\Gamma,h_2}$$

$$= \int_{\Omega} \omega_{\tau h_1 h_2}^k : d_t \pi_{\tau h_1 h_2}^k \, dx + \int_{\Gamma} f_{\tau h_1}^k \cdot z \, dS$$

for all $z \in V_{1,h_2}$.

The implementation of the approximation scheme was done in MATLAB in the spirit of [7, 3]. In this implementation, the nonlinear system of equations (5.7) is approximated with a Newton iteration and all occurring systems of linear equations are solved using MATLAB’s backslash operator. In our experiments the Newton scheme always terminated within at most 7 iterations to achieve an $\ell^2$ norm of the residual vector (defined through nodal basis functions) less than $10^{-2}$.

We used the scheme (5.7)–(5.8) to simulate the hard device loading of a thermally isolated body occupying the domain $\Omega$ depicted in Figure 1 and specified in the following example. The problem leads to the phenomenon of so-called “thermal necking” which has also been observed in [6, 13, 20].

**Setting.** Let $d := 2$, 
$$\Omega := ((-a/2, a/2) \times (-b/2, b/2)) \setminus (\text{conv}\{(0, c/2), (d/2, b/2), (-d/2, b/2)\} \cup \text{conv}\{(0, -c/2), (d/2, -b/2), (-d/2, -b/2)\})$$
\[ \Gamma_0 := \{ -a/2 \} \times (-b/2, b/2) \cup \{ a/2 \} \times (-b/2, b/2) \text{, and } \Gamma_1 := \partial \Omega \setminus \Gamma_0 \text{ with } a = 40 \text{mm,} \\
\text{so that } c = 2 \text{mm, } c = 1.8 \text{mm, and } d = 16 \text{mm. The material constants determining heat transfer are} \\
\hat{c}_v = 400 \text{J/kg K and } \mathcal{K} = \kappa I_{2 \times 2} \text{ for } \kappa = 80 \text{W/m K. The mass density is } \hat{g} = 8 \cdot 10^3 \text{kg/m}^3 \\
\text{so that } c_v = \hat{g} \hat{c}_v = 32 \cdot 10^3 \text{J/m}^3 \text{K. The Lamé coefficients are defined with the Young’s} \\
\text{modulus } E = 137 \text{GPa and the Poisson ratio } \nu = 0.3 \text{ through } \lambda = \nu E / ((1 + \nu)(1 - 2\nu)) \text{ and } \\
\mu = E / (2(1 + \nu)). \text{ The temperature-dependent set of admissible stresses is defined} \\
\text{through } \omega_{y,0} := 450 \text{MPa and a smooth function } \Upsilon \text{ satisfying } \Upsilon(\theta) = 1 \text{ for } \theta \leq 800 \text{K and} \\
\Upsilon(\theta) = 0.2 \text{ for } \theta \geq 820 \text{K.}
\]

With these definitions we try two different sets of data functions.

**Example 5.1** (Fast loading.). Set \( \alpha := 0, f := 0, g := 0, T := 2 \cdot 10^{-3} \text{s, and} \)
\[ u_D(t, x) := 10^2 t \text{ mm/s } \nu(x) \]
for \( t \in [0, T] \) and \( x \in \Gamma_0 \). As initial data we employ \( u_0 := 0, \pi_0 := 0, \text{ and } \theta_0 := 800 \text{K}. \)

**Example 5.2** (Slow loading.). Set \( \alpha := 0, f := 0, g := 0, T := 2s, \text{ and} \)
\[ u_D(t, x) := 10^{-4} t \text{ mm/s } \nu(x) \]
for \( t \in [0, T] \) and \( x \in \Gamma_0 \). As initial data we employ \( u_0 := 0, \pi_0 := 0, \text{ and } \theta_0 := 800 \text{K}. \)

We simplified this model problem by assuming that there exists a solution that reflects the symmetry of the problem (indicated by the dashed lines in Figure 1) and restricting to the part
\[ \Omega' := \left( \{ -a/2, 0 \} \times (0, b/2) \right) \setminus \text{conv}\{ (0, c/2), (0, b/2), (-d/2, b/2) \} \]
of the domain. This enforces us to implement gliding boundary conditions along the sides
\( (-a/2, 0) \times \{ 0 \} \) and \( \{ 0 \} \times (0, c/2) \), i.e., to impose (homogeneous) Dirichlet conditions on
one of the two components of the displacement field \( u \) and a (homogeneous) Neumann condition on the remaining component.

For a triangulation of \( \Omega' \) into 1280 triangles obtained from three uniform refinements
of the coarse triangulation of \( \Omega' \) into 20 triangles shown in Figure 1 and used for both
equations (5.7) and (5.8), we employed the time-step size \( \tau = 10^{-2} T/2 \). In Figures 3 and 4 we plotted respectively the evolution of the modulus of the plastic strain and the
temperature on the deformed body defined by the deformations \( u_{r_1 h_2}(t, \cdot) \) corresponding to the loading \( |u_D(t)| = 4, 8, 12, 16, 20 \cdot 10^{-2} \text{mm} \) (i.e., for \( t = 4, 8, 12, 16, 20 \cdot 10^{-4} \text{s} \)) obtained with the scheme (5.7)-(5.8) and the loading defined in Example 5.1. For a better visualization we magnified the displacement by a factor 5. We observe that the occurrence of plastic material behavior is accompanied by a local rise of the temperature leading in turn to a softening of the material. This softening effect due to an increasing temperature

![Figure 1. Graphical description of the model problem and coarse triangulation of the computational domain. The body is initially "hot" and thermally isolated on all sides.](image-url)
is also illustrated in the plots of Figure 2 where we plotted the discrete power of external mechanical forces

\[ P^k_{\tau h_1h_2}(d_tu^k_{\tau h_1h_2}, \sigma^{nor,k}_{\tau h_1h_2}, \theta^k_{\tau h_1h_2}) = \langle \sigma^{nor,k}_{\tau h_1h_2}, d_tu^k_{\tau h_1h_2} \rangle \Gamma_0 \]

defined in (4.15) as a function of the loadings defined in Example 5.1 and 5.2. For the slow process, diffusion of heat within the isolated body is much faster and hence the (non-uniform) yield stresses decrease slower in the plastic region leading to a significantly reduced softening behavior. The evolution of the modulus of the plastic strain and the temperature for the slow loading experiment defined in Example 5.2 is displayed in Figures 5 and 6 and we observe that owing to the more equally distributed temperature, the deformation of the right end \( \{0\} \times (0,c/2) \) of the body is less significant than for the fast process defined in Example 5.1.

\[
\begin{align*}
|u_{D}(t)| & \quad [\text{mm}] \\
P_{\tau h_1h_2}(t) & \quad [\text{J}] \\
\end{align*}
\]

**Figure 2.** Power of external mechanical forces versus applied load for fast (left plot) and slow (right plot) loading. A softening effect due to the increase in temperature can be observed for \(|u_{D}(t)| \geq 0.1\text{mm}\). The softening effect is more significant in the case of fast loading.

Finally, to study the accuracy of our numerical scheme, we plotted in Figure 7 the effect of numerical dissipation represented by

\[ \xi_{\tau h_1h_2}(t_K) := \frac{E^K_{\text{tot}} - E^0_{\text{tot}} - \tau \sum_{k=1}^{K} P^k_{\tau h_1h_2}(d_tu^k_{\tau h_1h_2}, \sigma^{nor,k}_{\tau h_1h_2}, \theta^k_{\tau h_1h_2})}{\tau \sum_{k=1}^{K} P^k_{\tau h_1h_2}(d_tu^k_{\tau h_1h_2}, \sigma^{nor,k}_{\tau h_1h_2}, \theta^k_{\tau h_1h_2})} \]

where \( E^k_{\text{tot}} := \int_{\Omega} c_v \theta^k_{\tau h_1h_2} \, dx + \frac{1}{2} C^{-1} \sigma^k_{\tau h_1h_2} : \sigma^k_{\tau h_1h_2} \, dx \). The quantity measures the failure of a discrete version of the continuous energy balance. Owing to the implicit discretization of the heat equation and the explicit treatment of the temperature dependence in the variational inclusion, numerical dissipation occurs, cf. Proposition 4.2. The results shown in Figure 7 indicate that this effect is comparatively small and that \( \max_{t \in (0,2)} |\xi_{\tau h_1h_2}(t)| \) decays linearly to 0 with \( h \) as \( h \to 0 \) in our model problem and for the employed time-step size \( \tau = h 20 \cdot 10^{-6}\text{s/mm} \). This rate is in correct agreement with the assertion of Proposition 4.2.

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Figure 3. Deformation and modulus of plastic strain for $|u_D(t)| = 4, 8, 12, 16, 20 \cdot 10^{-2}$mm (displacement is multiplied by factor 5) in the fast loading experiment defined in Example 5.1.

Figure 4. Deformation and temperature for $|u_D(t)| = 4, 8, 12, 16, 20 \cdot 10^{-2}$mm (displacement is multiplied by factor 5) in the fast loading experiment defined in Example 5.1.
Figure 5. Deformation and modulus of plastic strain for $|u_D(t)| = 4, 8, 12, 16, 20 \cdot 10^{-2}\text{mm}$ (displacement is multiplied by factor 5) in the slow loading experiment defined in Example 5.2.

Figure 6. Deformation and temperature for $|u_D(t)| = 4, 8, 12, 16, 20 \cdot 10^{-2}\text{mm}$ (displacement is multiplied by factor 5) the slow loading experiment defined in Example 5.2.
Figure 7. Numerical dissipation for mesh-sizes $h = 2^{-0}, 2^{-1}, 2^{-2}$ mm and $\tau = h \cdot 20 \cdot 10^{-6}$ s/mm in the model example with loading defined by (a).

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