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MCRE-based finite element model updating: Cast3M implementation

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Abstract

In structural engineering, the search for computational models capable of making realistic predictions capturing varied physical phenomena while maintaining simplicity and reliability has gained wide attention of the scientific community. Some outcomes of this effort are the finite element model updating techniques, which consists of using inverse analysis to find realistic values for the set of input parameters. The Modified Constitutive Relation Error (MCRE) has proved to be efficient for model updating in many engineering applications. The central idea of this technique is to formulate parameter identification as a well-posed optimization problem. In general, for each new MCRE application, new formulations need to be deduced and implemented. Despite the specifics of each case, there are standard features that can be abstracted and placed in a single framework. In the present work, we abstract and materialize those features into a new computational framework using Cast3M (an open-source high-level toolbox for finite elements computation). Using typical examples from structural engineering, we test the framework's efficiency and highlight its limitations. The results show that the proposed open-source code allows the identification of physical parameters for finite element models, such as stiffness, as long as physical and geometric linearity conditions remain valid. In addition, elastic inter-element interfaces can be included without significant changes. The benefits of the present study are twofold: (i) source codes are made available and can be used as learning support, in particular for newcomers, and (ii), it can be used as a starting point for new developments in the field of MCRE-based approaches.

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1. Introduction

Modelling and simulation of structural systems are crucial activities in modern engineering and science for several reasons. For instance, at the design stage, engineers can answer particular questions about structures that have not yet come into existence. In the construction phase, these activities allow engineers to plan and execute each step to optimize costs and gain productivity. In the service phase, the same activities provide information on the instantaneous functioning of the system and thus make the decision-making process feasible. In scientific investigations, it has become common to use modelling techniques to study new phenomena in different areas of knowledge [1]. Modelling and simulation activities have gained such prominence along the last century that they are currently attributed the title of the third pillar of science, alongside theory and experimentation [2].

Among the various specialities present in modelling activities, one is of particular interest for the present work, namely, the *verification*. This speciality is dedicated to checking if the results predicted by the models correspond to observations. Ideally, the closer to reality, the more reliable the model becomes. However, in usual-life situations, accurately predicting the behaviour of structural systems is not self-evident. A new technique, called *model updating* or *parameter identification*, has emerged over the past few decades in the quest for better predictions. This technique determines which set of input parameters is most appropriate so that the corresponding model approaches reference measures in a particular scenario. The advantage is once these parameters are identified, structural predictions may perform better in scenarios other than those used to make the identification.

The literature presents various techniques capable of updating finite element models [3, 4]. These techniques may be understood according to two classes: in the *direct* techniques, the model parameters are identified relying primarily on linear algebra principles [5, 6]; on the other hand, in the *indirect* or *parametric* techniques, the model parameters are identified using consistent mechanical quantities [7, 8]. The latter is best indicated when the input parameter of interest represents a physical quantity, such as stiffness or mass. The technique employed in the present study relies on the formalism

of the Constitutive Relation Error (CRE) theory and belongs to the class of indirect methods.

The CRE formulation was initially proposed to estimate errors in finite dimension spaces [9]. Soon after, its augmented version, namely the MCRE (Modified Constitutive Relation Error), was successfully applied in finite element model updating [10]. Since then, MCRE-based techniques have been refined and expanded to different engineering fields, including, but not limited to, mechanical engineering [11], acoustics [12], automotive industry [13], aerospace structures [14, 15], topology optimization [16] and civil engineering [17, 18, 19, 20]. It is worth mentioning that inherent uncertainties can also be considered in model updating [21, 22, 23].

In modern research involving computational mechanics, the open/collaborative coding approach has increasingly gained ground in academia and industry. The joint effort of several collaborators worldwide has ensured the development of multiobjective numerical platforms such as MFEM [24], FEniCS [25], FreeFem++ [26], deal.II [27], Cast3M [28, 29], OpenFOAM [30], among others. Despite the remarkable advances in this field, open-source MCRE-based computer frameworks are still rare. The consequence is that each time a user wants to use an MCRE-based technique, a new code must be created starting from scratch.

To address this need, in the present work, we propose an abstraction of the essential elements related to usual MCRE techniques and materialize them in an open-source framework. The input data is formed by a finite set of eigenfrequencies and corresponding modal shapes. The constitutive material is assumed linear-elastic. All implementations are carried out into Cast3M, which is a general-purpose code for solving partial differential equations using the finite element method. Cast3M is distinguished from other finite element toolboxes by its intuitive lexicon and syntax, providing users with a fast learning tool. This toolbox is developed and made available by the French Atomic Energy Commission (CEA), used in industry, research, and education [31, 32, 33, 34].

The proposed framework can be helpful to users at different levels. Newcomers to the finite element model updating field may find helpful information in the resulting sources codes once they are fully provided with considerable commented sections. They may be used in extended studies in structural analysis where engineers may be assigned to do extensions such as multiple load-cases, distinct cost functions and structural parameters. Further possibilities include using the codes as a starting point for more complex FE

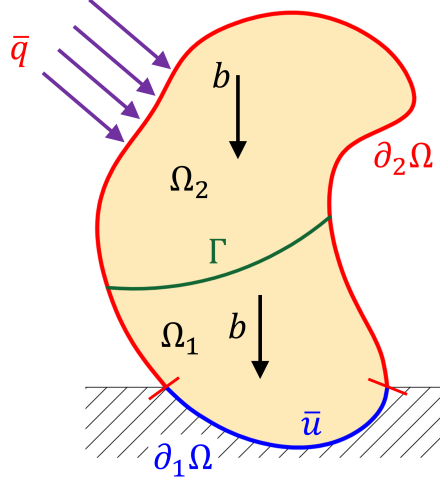


Figure 1: Solid associated to identification process. For this case, $\Omega_1 \cup \Omega_2 = \Omega$ and $\partial_1 \Omega \cup \partial_2 \Omega \cup \Gamma = \partial \Omega$.

72 model updating scenarios. Experienced users may go further, extending to
 73 the domain of structural health monitoring and even design of experiments.

74 2. Formulating the identification problem

75 2.1. The reference problem on the MCRE formalism

76 Let a structure be represented by $\Omega \subset \mathbb{R}^3$, with boundary, $\partial \Omega$. The
 77 structural outer surface is divided into three parts. Parts one and two are
 78 regions where the interaction between the structure and the environment
 79 occurs: kinematic constraints $\bar{\mathbf{u}}$ on a part $\partial_1 \Omega$ and traction forces $\bar{\mathbf{q}}$ on $\partial_2 \Omega$.
 80 The third part, Γ , is the region among sub-domains of the structure so that
 81 $\partial_1 \Omega \cup \partial_2 \Omega \cup \Gamma = \partial \Omega$. The situation is illustrated in Figure 1. Assuming that
 82 the entire domain follows the principles of mechanics, we are interested in
 83 identifying the structural elastic properties.

84 The first key aspect in formulations that follow the CRE prerogatives
 85 is separating governing equations into two sets: the *reliable* set includes all
 86 equations that must be strictly respected, and the *unreliable* set includes
 87 only the equations susceptible to be doubtful. The division of these sets is
 88 not unique, and it is up to the analyst to make the most appropriate choice
 89 for the case to be dealt with. In the present study, the following separations
 90 are made.

91 1. *Reliable* equations set:

- Kinematic boundary conditions.

$$\mathbf{u} \Big|_{\partial_1 \Omega} = \bar{\mathbf{u}} \quad (1)$$

- Dynamic equilibrium.

$$\begin{aligned} \int_{\Omega} \rho \ddot{\mathbf{u}} \cdot \mathbf{u}^* d\Omega_i + \int_{\Omega} \boldsymbol{\sigma} : \boldsymbol{\varepsilon}^* d\Omega = \int_{\Omega} \mathbf{b} \cdot \mathbf{u}^* d\Omega_i + \\ + \int_{\partial_2 \Omega} \boldsymbol{\sigma} \mathbf{n} \cdot \mathbf{u}_i^* d\partial\Omega \end{aligned} \quad (2)$$

- Force boundary conditions.

$$\boldsymbol{\sigma} \mathbf{n} \Big|_{\partial_2 \Omega} = \bar{\mathbf{q}} \quad (3)$$

92 2. *Unreliable* equations set:

- Constitutive relation.

$$\mathbf{f}(\boldsymbol{\sigma}, \boldsymbol{\varepsilon}(u)) = \boldsymbol{\sigma} - \mathbb{C}(\theta) : \boldsymbol{\varepsilon} \quad (4)$$

- Collected measures.

$$\mathbf{r}(\mathbf{u}, \tilde{\mathbf{u}}) = \mathbf{u} - \tilde{\mathbf{u}} \quad (5)$$

93 with $\mathbb{C}$ the Hookean stiffness operator specified by the material properties
 94 stored at θ , $\mathbf{u}$ is the displacement vector, $\boldsymbol{\sigma}$ the stress tensor, $\boldsymbol{\varepsilon}$ is the infinitesimal strain tensor, ρ the mass density, $\tilde{\mathbf{u}}$ represents the collected measures.
 95 The unreliable quantities are the constitutive relation since they may not be
 96 representative enough of the real behaviour, and the measurements because
 97 they carry errors with them. Then, the identification problem can be formulated by comparing the results predicted by the model and the experimental
 98 data. The reliable set is used to build the kinematic and static admissible
 99 spaces:
 100
 101

$$\mathcal{U} = \{\mathbf{u} \in H^1(\Omega) : \mathbf{u} \Big|_{\partial_1 \Omega} = \bar{\mathbf{u}}\} \quad (6)$$

$$\mathcal{D} = \{\boldsymbol{\sigma} \in H^{div}(\Omega) : \text{Equation (2) holds, } \boldsymbol{\sigma} \mathbf{n} \Big|_{\partial_2 \Omega} = \bar{\mathbf{q}}\} \quad (7)$$

102 The second key aspect in CRE-based formulations is to relate the unreli-
 103 able quantities so that they are verified as well as possible. One alternative is
 104 by minimizing a functional comprising the terms considered uncertain. Here,
 105 this functional is written as follows:

$$J(\mathbf{u}, \boldsymbol{\sigma}, \theta) = \int_{\Omega} (\boldsymbol{\sigma} - \mathbb{C}(\theta)\boldsymbol{\varepsilon}) : \mathbb{C}^{-1}(\boldsymbol{\sigma} - \mathbb{C}(\theta)\boldsymbol{\varepsilon}) d\Omega + \frac{r}{2(1-r)} \|\mathbf{u} - \tilde{\mathbf{u}}\| \quad (8)$$

106 The role played by the parameter $r \in (0, 1)$ is twofold. It makes the
 107 scale order compatibility between the quantities involved and controls the
 108 importance given to the experimental measures within the functional.

109 Then, the parameter identification problem is written as:

$$\begin{aligned} &\text{Find } (\mathbf{u}, \boldsymbol{\sigma}, \theta) \text{ that minimizes } J(\mathbf{u}, \boldsymbol{\sigma}, \theta) \\ &\text{Such that } (\mathbf{u}, \boldsymbol{\sigma}) \in \mathcal{U} \times \mathcal{D} \end{aligned} \quad (9)$$

110 Rather than express the entire problem at once, it is convenient to write
 111 it down into two steps as follows:

$$\min_{\mathbf{u}, \boldsymbol{\sigma}, \theta} J(\mathbf{u}, \boldsymbol{\sigma}, \theta) \iff \min_{\theta} \min_{\mathbf{u}, \boldsymbol{\sigma}} J(\mathbf{u}, \boldsymbol{\sigma}, \theta) \quad (10)$$

112 In practice, this choice simplifies the formulation that can be solved in two
 113 sequential steps. First, the pair of admissible fields optimally fit the fixed-
 114 parameter set θ is obtained. Then, an identification process is performed
 115 based on these admissible fields.

116 2.2. Obtaining mechanical admissible fields

117 For a given θ , the mechanical admissible fields are obtained by:

$$\begin{aligned} &\min J_1(\mathbf{u}, \boldsymbol{\sigma}) + J_2(\mathbf{u}) \\ &\text{s.t. } \mathbf{u} \in \mathcal{U} \text{ and } \boldsymbol{\sigma} \in \mathcal{D} \end{aligned} \quad (11)$$

where,

$$J_1(\mathbf{u}, \boldsymbol{\sigma}) = \frac{1}{2} \int_{\Omega} (\boldsymbol{\sigma} - \mathbb{C}\boldsymbol{\varepsilon}) : \mathbb{C}^{-1}(\boldsymbol{\sigma} - \mathbb{C}\boldsymbol{\varepsilon}) d\Omega \quad (12)$$

$$J_2(\mathbf{u}) = \frac{r}{2(1-r)} \|\mathbf{u} - \tilde{\mathbf{u}}\| \quad (13)$$

118 The functional J_1 expresses the disparity of the stiffness properties, whereas
 119 J_2 represents a deviation from the experimental measures. The minimization
 120 of $J = J_1 + J_2$ allows verifying the unreliable equations as best as possible.
 121 Thus, all the available data are used to build the desired mechanical fields.

122 2.3. Identifying the optimal parameters

123 To each θ , it is necessary to associate a non-negative scalar that represents
 124 its quality level. Here, we use the same functional J , with the particularity
 125 that its value is calculated from the fields previously obtained (Equation
 126 (11)). In other terms:

$$F(\theta) = J(\mathbf{u}(\theta), \boldsymbol{\sigma}(\theta)) \quad (14)$$

127 With this definition, the lower the value of F , the better θ becomes.
 128 Then, the identification problem consists in finding the best parameters θ^*
 129 for the model by minimizing the cost function F :

$$\theta^* = \underset{\theta}{\operatorname{argmin}} F(\theta) \quad (15)$$

130 2.4. Algebraic description of the problem

131 The equations will be solved using the displacement-based finite element
 132 method (FEM) in this study. This choice does not represent any difficulty
 133 because the admissible stress field can be associated with an admissible dis-
 134 placement field, as follows:

$$\boldsymbol{\sigma}(\mathbf{v}) = \mathbb{C}\boldsymbol{\varepsilon}(\mathbf{v}) \quad (16)$$

135 Considering the FEM formalism, the set of displacements fields can be
 136 written as:

$$\mathbf{u}(x) = \mathbf{N}(x)\mathbf{U}, \quad \mathbf{v}(x) = \mathbf{N}(x)\mathbf{V} \quad (17)$$

137 where $\mathbf{N}(x)$ is the shape functions matrix, $\mathbf{U}$ and $\mathbf{V}$ are unknown nodal
 138 displacements associated to $\mathbf{u}$ and $\mathbf{v}$. Then, equation (12) can be written as:

$$J_1(\mathbf{U}, \mathbf{V}) = \frac{1}{2}(\mathbf{V} - \mathbf{U})^T \mathbf{P}(\mathbf{V} - \mathbf{U}) \quad (18)$$

139 where P is the stiffness matrix corresponding to the region to be identified,
 140 including interfaces considered to be elastic. Let $\tilde{\Pi}$ be a projector operator to
 141 assure the spatial correspondence between U and $\tilde{U}$. Then, the experimental
 142 counterpart $\|\mathbf{u} - \tilde{\mathbf{u}}\|$ can be defined in a quadratic form such as:

$$J_2(U, \tilde{U}) = \frac{r}{2(1-r)}(\tilde{\Pi}U - \tilde{U})^T G_u (\tilde{\Pi}U - \tilde{U}) \quad (19)$$

143 where G_u carries the stiffness terms related to the nodes where the measure-
 144 ments have been taken.

145 The identification is based on the free-vibration modes of the structure.
 146 These modes can be estimated under the assumption of sinusoidal time func-
 147 tions: $u(x, t) = U(x)\sin(\omega t)$, $v(x, t) = V(x)\sin(\omega t)$. In this cases, equation
 148 (2) becomes:

$$KV - \omega^2 MU = F \quad (20)$$

149 where ω is the structural vibration frequency and F is the external excitation
 150 force. For free-vibration problems, $F = 0$.

151 The search for admissible mechanical fields can be written as a con-
 152 strained optimization problem. Introducing the Lagrange multipliers, λ , the
 153 quantity to be minimized is defined as:

$$\begin{aligned} L(V, U, \lambda) &= \frac{1}{2}(V - U)^T P (V - U) \\ &+ \frac{r}{2(1-r)}(\tilde{\Pi}U - \tilde{U})^T G_u (\tilde{\Pi}U - \tilde{U}) + \lambda^T (KV - \omega^2 MU) \end{aligned} \quad (21)$$

For a fixed θ , the stationarity is achieved when:

$$\frac{\partial L}{\partial U} = P(U - V) + \frac{r}{(1-r)}\tilde{\Pi}^T G_u (\tilde{\Pi}U - \tilde{U}) - \omega^2 M\lambda = 0 \quad (22)$$

$$\frac{\partial L}{\partial V} = P(U - V) - K\lambda \quad (23)$$

$$\frac{\partial L}{\partial \lambda} = KV - \omega^2 MU = 0 \quad (24)$$

154 These equations can be written as a linear system:

$$[A]X = Y \quad (25)$$

155 where,

$$[A] = \begin{bmatrix} P & \frac{r}{(1-r)} \tilde{\Pi}^T G_u \tilde{\Pi} & -\omega^2 M \\ P & 0 & -K \\ -K & K - \omega^2 M & 0 \end{bmatrix} \quad (26)$$

$$X = \begin{Bmatrix} U - V \\ U \\ \lambda \end{Bmatrix} \quad (27)$$

$$Y = \begin{Bmatrix} \tilde{\Pi}^T G_u \tilde{U} \\ 0 \\ 0 \end{Bmatrix} \quad (28)$$

156 The same function was used to define both the admissible field search and
 157 the identification problem. This implies the direct access to the gradient of
 158 function (14), as follows:

$$F(\theta) = L(U(\theta), V(\theta), \lambda(\theta), \theta) \quad (29)$$

From the stationarity of L , it comes:

$$\frac{\partial F}{\partial \theta} = \underbrace{\frac{\partial L}{\partial U}}_{=0} \frac{\partial U}{\partial \theta} + \underbrace{\frac{\partial L}{\partial V}}_{=0} \frac{\partial V}{\partial \theta} + \underbrace{\frac{\partial L}{\partial \lambda}}_{=0} \frac{\partial \lambda}{\partial \theta} + \frac{\partial L}{\partial \theta} \quad (30)$$

$$\frac{\partial F}{\partial \theta} = \frac{\partial L}{\partial \theta} = \frac{1}{2} (V - U)^T \frac{\partial P}{\partial \theta} (V - U) + \lambda^T \frac{\partial K}{\partial \theta} V \quad (31)$$

159 This expression can be used to construct minimum search algorithms
 160 based on gradients.

161 3. Proposing the algorithm to solve the problem

162 3.1. Initiate model

163 In this step, the initial information that usually defines a finite element
 164 model should be provided, such as the geometric support of the structure,
 165 the finite element discretization (mesh) and the set of boundary conditions.
 166 It is also necessary to provide the set of measures that will be used as a
 167 reference for the identification process. Such measures are usually obtained
 168 in two ways: through previous numerical simulations of the structure in a

reference state (synthetic measurements) or direct measurements on physical structures in controlled locations, laboratories, or exposed to the environment (experimental measurements).

Distinct objective functions can be defined as a function of the reference quantities (e.g. [22, 35]). In the present work, the reference quantities are the vibration modes of the structure obtained synthetically using a dedicated FEM module (more details in Section 4).

3.2. *Initiate parameter set*

This step consists in choosing the initial values for the set of parameters that will be identified. Since the identification process is based on a Newton-type gradient method, the initial values influence the amount of iterations that will be necessary to obtain convergence. To improve efficiency, the analyst can benefit from previous information that one has about the structure, such as parameters obtained from preceding simulations, estimates based on empirical knowledge, statistics data and even engineering heuristics. It is worth noting that the correct value of the parameter will be provided by the algorithm at the end of the identification process. For this reason, at this stage, the analyst may privilege obtaining reasonable orders of magnitude for the initial values instead of precise estimates.

The choice of the parameters to be identified depends on the studied scenario. For example, it is known that in a given structure, zones of eventual damage are accompanied by local losses of stiffness. Thus, a correlation between these two characteristics can be established for model identification purposes. In the present study, the stiffness (linear or angular) is chosen as the parameter to be identified. This choice does not imply loss of generality since CRE theory allows much more general choices for different constitutive models [13, 36].

3.3. *Calculate admissible fields*

From a known set of material parameters, the corresponding admissible nodal fields (U, V, λ) are determined by solving equation (25). This linear system is three times the size of the classic finite element problem. This can limit problems with a high number of degrees of freedom, particularly in three-dimensional industrial models. However, it should be noted that, for identification purposes, a reduced number of finite elements can be used efficiently. There is also the possibility of model reduction, using modal projections, among other techniques, that reduce the order of the linear system

205 to be solved. Here, for the sake of simplicity in coding, it is used the full
 206 version of equation (25).

207 3.4. Calculate global MCRE

208 The global MCRE is obtained from equations (18) and (19) such as:

$$J(\mathbf{U}, \mathbf{V}, \tilde{\mathbf{U}}) = J_1(\mathbf{U}, \mathbf{V}) + J_2(\mathbf{U}, \tilde{\mathbf{U}}) \quad (32)$$

209 The result is a scalar quantity necessary for the convergence test.

210 3.5. Convergence criterion

211 There are two convergence tests immediately available. The first one
 212 assumes convergence is achieved whenever:

$$J(\mathbf{U}, \mathbf{V}, \tilde{\mathbf{U}}) < \xi_1 \quad (33)$$

213 The second assumes convergence is achieved when no improvement is
 214 observed for a limited number of consecutive iterations (5 in our tests), that
 215 is:

$$||J_i(\mathbf{U}, \mathbf{V}, \tilde{\mathbf{U}}) - J_{i-1}(\mathbf{U}, \mathbf{V}, \tilde{\mathbf{U}})|| < \xi_2 \quad (34)$$

216 where ξ_1 and ξ_2 are small positive values. The most appropriate choice may
 217 depend on the case handled by the analyst.

218 3.6. Calculate CRE field

219 In practical applications, for the sake of efficiency, it may be beneficial
 220 not to update all stiffness parameters simultaneously. When the region to
 221 be identified is not known *a priori*, a simple strategy can be drawn based
 222 on equation (18). It carries the information about how well the material pa-
 223 rameters of the model correspond to reality. So, the structure can be divided
 224 into sub-regions, and the quantity of J_1 for each of them can be obtained.
 225 Using relative comparisons, regions with higher modelling errors will indicate
 226 higher values of J_1 , and therefore they should have their parameters updated
 227 first. Suppose that n sub-regions were defined for the calculation of J_1 . In
 228 this case, the indicator β is written as:

$$\beta_j = \frac{J_1(\mathbf{U}, \mathbf{V})_j}{\sum_{j=1}^n J_1(\mathbf{U}, \mathbf{V})_j} \quad (35)$$

229 The higher the value of this indicator, the greater the participation of the
 230 corresponding region in the global error, and consequently, it should receive
 231 priority for updating. This strategy can be automated to work adaptively.

232 3.7. Update material parameters

233 The regions selected in the previous step will have their material param-
 234 eters updated. From a set of known values θ_i , one attempts to determine an
 235 improved set θ_{i+1} . There are different ways available for this purpose, such
 236 as Newton or BFGS method. Here, we use a simple steepest gradient, such
 237 that;

$$\text{Compute } \nabla\theta \text{ from equation (31)} \quad (36)$$

$$\text{Compute } s \text{ solving } \min_s F(\theta - s\nabla\theta) \quad (37)$$

$$\Delta\theta_{i+1} = -s\nabla\theta \quad (38)$$

$$\theta_{i+1} = \theta_i + \Delta\theta_{i+1} \quad (39)$$

238 The flowchart in Figure 2 shows how these tasks are arranged. This
 239 framework can be implemented using any FEM purpose language. Here,
 240 Gibiane version 2020 was chosen for all applications [29].

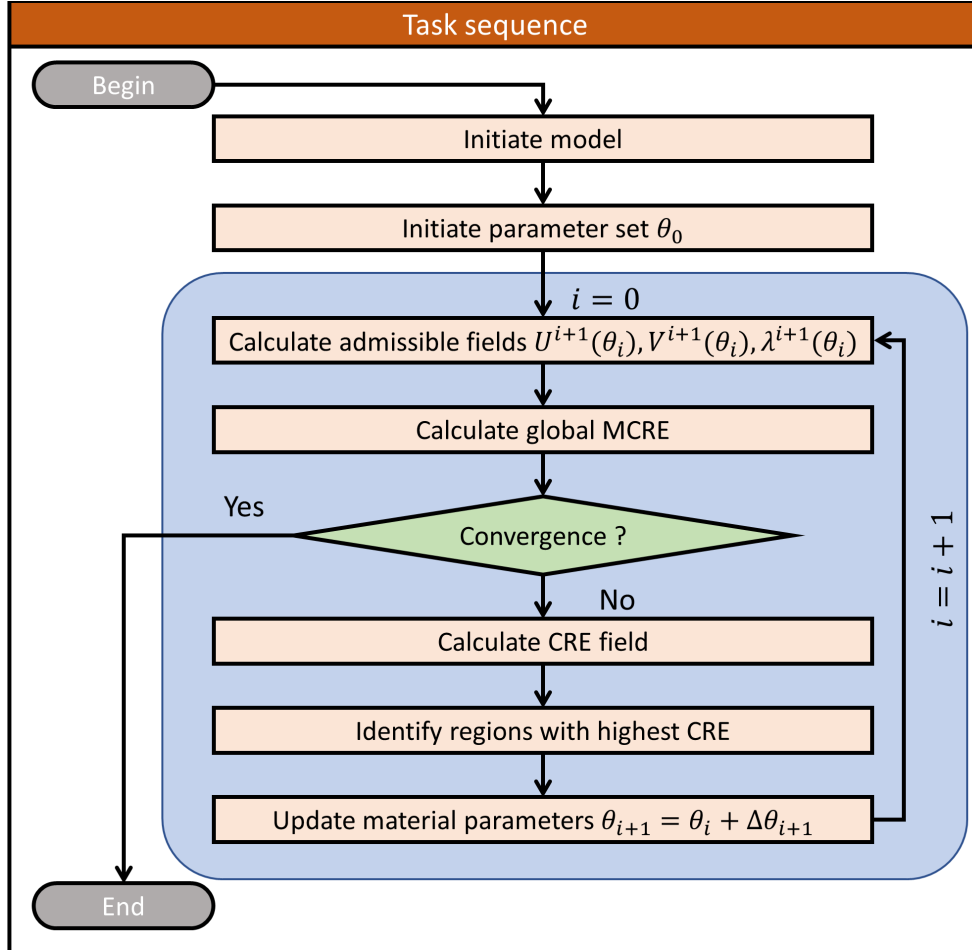


Figure 2: Task sequence for solving the identification problem.

241 4. Cast3M implementation

242 Four modules were designed to facilitate the application and expansion
 243 of the proposed framework. These modules, specified through independent
 244 Gibiane files, contain information related to geometry, models and materials,
 245 reference measures, and model updating core processing. For each applica-
 246 tion, these files must be filled in with the correspondent information and then
 247 executed separately in order to produce their outputs. The communication
 248 between the different modules is done via writing and reading commands
 249 (SAUV, REST), as shown in Figure 3.

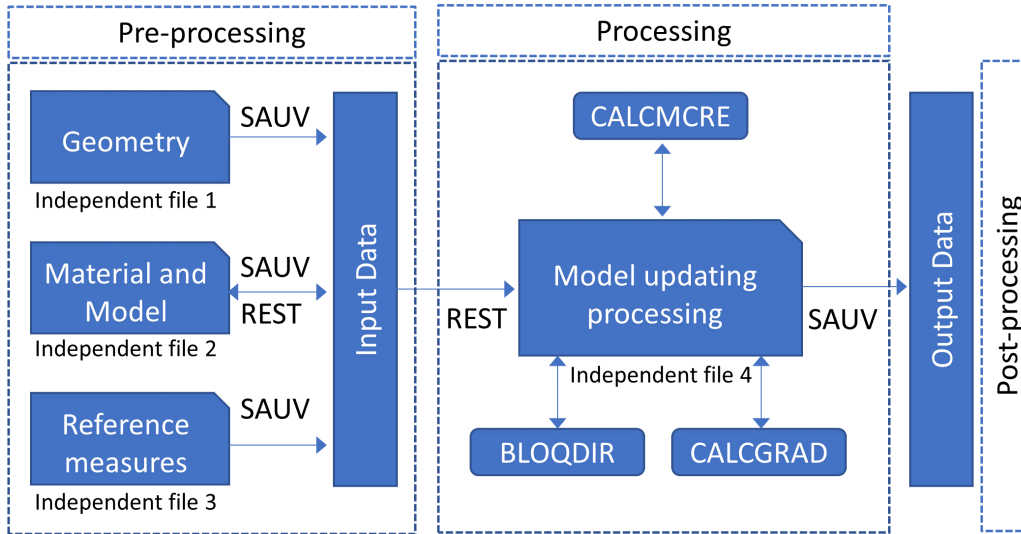


Figure 3: Communication diagram.

250 4.1. Geometry

251 In this module, all information about the geometry of the finite element
252 model to be updated must be provided. All the options available for reticular,
253 planar and volumic elements remain valid.

```

*****
* Defining the spatial dimension and the
* the root finite elements library
'OPTI' 'DIME' 3 'ELEM' 'CUB8' ;
*****
* Number of elements allocated to each pillar
NEL = 6;
* Geometric nodes
P1 = 0.0000 0.0000 0.0000;
P2 = 0.0000 0.0000 3.0000;
P3 = 0.0000 0.0000 6.0000;
P4 = 0.0000 0.0000 9.0000;
* Creating pillars
L1 = 'DROI' NEL P1 P2;
L2 = 'DROI' NEL P2 P3;
L3 = 'DROI' NEL P3 P4;
* Creating the set of pillars to be updated
PI_UPD = L1 'ET' L2;
* Pillars not to be updated
PI_N_UPD = L3;
*
*****

```

Figure 4: Illustration: three-pillar geometry definition.

254 The regions of the model that will be updated and those that will not must
255 be adequately identified. As an illustration, consider a structure consisting of
256 three pillars, three metres long each, aligned along the z-direction. Suppose
257 we want to update only two of the three pillars (L1, L2). In this case, Figure 4
258 shows how the geometry file would be filled. Dedicated procedures and other
259 external subroutines calls can be used inside this module for more complex
260 geometries.

261 4.2. Material and Model

262 In this module, it is necessary to inform the constitutive models and the
263 kinematic hypotheses involved (beam, plate, shell, etc.), as well as the nec-
264 essary characteristics of each one. As previously stated, only geometrically
265 linear elastic models should be considered.

266 As in the case of geometry, each region that will be updated, and those
 267 that will not, must be adequately identified. In the example of the three
 268 pillars, the proper way to fill out this file is the way indicated in Figure 5.

```
*****
*Material properties
MOD1 = 3.2E10;
PES1 = 2500;
COE1 = 0.2;
*Cross section properties
PILSEC = 0.16;
OY = 1. 0. 0.;
IN_OY = 2.1E-3;
IN_OZ = 2.1E-3;
IN_TOR= 4.0E-3;
* Model and material instances to be updated
MOD1 = 'MODEL' PI_UPD 'MECANIQUE'
      'ELASTIQUE' 'POUT';
MAT1 = 'MATE' MOD1 'YOUN' MOD1 'NU' COE1
      'RHO' PES1;
CAR1 = 'CARA' MOD1 'SECT' PILSEC 'INRY' IN_OY
      'INRZ' IN_OZ 'TORS' IN_TOR 'VECT' OY;
MAT1 = MAT1 'ET' CAR1;
* Model and material instances unchanged
MOD2 = 'MODEL' PI_N_UPD 'MECANIQUE'
      'ELASTIQUE' 'POUT';
MAT2 = 'MATE' MOD2 'YOUN' MOD1 'NU' COE1
      'RHO' PES1;
CAR2 = 'CARA' MOD2 'SECT' PILSEC 'INRY' IN_OY
      'INRZ' IN_OZ 'TORS' IN_TOR 'VECT' OY;
MAT2 = MAT2 'ET' CAR2;
*
*****
```

Figure 5: Illustration: three pillar model and material definition.

269 4.3. Reference Measures

270 In this module, information on the reference measures (frequencies and
 271 mode shapes) should be provided. They can be obtained from experiments or

272 other numerical simulations. It is worth mentioning that the analyst should
273 be careful about the boundary conditions because they directly influence
274 the physical parameter to be identified, in particular within a low-frequency
275 spectrum.

276 In the case of the pillar model, assuming a sinusoidal shape for the first
277 vibration mode and a frequency of $0.83Hz$, Figure 6 illustrates how the
278 measures could be manually set up. The reference measures are always stored
279 in TABLE format, even if it contains only one input.

```
*****  
*Reference modes  
*  
STR = L1 'ET' L2 'ET' L3;  
C1 = 'COOR' STR 3;  
C2 = 'SIN ' ((C1/9.)*(180./3.14));  
U1 = 'CHAN' C2 'COMP' 'UX';  
U2 = 0.*('CHAN' C2 'COMP' 'UY');  
U3 = 0.*('CHAN' C2 'COMP' 'UZ');  
U = U1 'ET' U2 'ET' U3;  
*  
FREQREF = TABLE;  
MODEREF = TABLE;  
*  
FREQREF . 1 = 0.83 ;  
MODEREF . 1 = U;  
*  
RES1 = 'TABLE';  
RES1 . 'NB_OF_REFERENCE_MODES' = 1;  
RES1 . 'REFERENCE_FREQUENCIES' = FREQREF;  
RES1 . 'REFERENCE_MODE' = MODEREF;  
*  
*****
```

Figure 6: Illustration: defining the first reference mode and frequency for the three pillar model.

280 In the case the reference modes come from experiments, the data must be
281 organized in the form CHPOINT before being stored in the reference table.

282 4.4. Model Updating Processing

283 The three previous modules serve to organize the information in a struc-
284 tured manner so that the processing module can be carried out appropriately.
285 The present module corresponds to the implementation of the tasks shown
286 in Figure 2, which requires the use of two three auxiliary procedures, which
287 are described below.

288 4.4.1. Procedure: *CALCMCRE*

289 This procedure takes as input the reference measures, geometry, model
290 and material properties and calculates the admissible nodal fields (Equation
291 (25)).

292 4.4.2. Procedure: *CALCGRAD*

293 This procedure takes the admissible fields and current material properties
294 as input and provides the calculation of the gradient of the quantities to be
295 updated (Equation (31)).

296 4.4.3. Procedure: *BLOQDIR*

297 This procedure is used to impose the boundary conditions on the admis-
298 sible fields before the linear system solution in *CALCMCRE*. Here we have
299 opted for the penalization method so that the standard algorithm for solving
300 systems of equations, available in Cast3M, can be used directly. However,
301 other ways, such as Lagrange multipliers, are possible. In this case, attention
302 should be paid to possible conflicts in managing internal software indexes.

303 5. Numerical examples

304 In this Section, typical examples from the engineering field illustrate how
305 the framework discussed in the previous sections is helpful. The correspond-
306 ing source codes were implemented in Gibiane language (Version 2020) and
307 can be found on the publisher’s website.

308 5.1. Revealing poorly modelled regions

309 One of the valuable features of the proposed framework is the ability to
310 indicate poorly modelled regions, regions in which the values of material prop-
311 erties (such as stiffness) are far from their reference values. To illustrate this
312 ability, we use the Mottershead beam [3] with the following reference param-
313 eters: $L = 0.7m$, $EI = 4560Nm^2$, $\rho = 2860kg/m^3$, $k_r = 1.0 \times 10^5 Nm/rad$

314 (angular stiffness) and $k_t = 4.0 \times 10^7 N/m$ (translational stiffness). The
 315 discrete model was divided into eleven regions, being ten elementary re-
 316 gions, each containing three finite elements, and an interface region where
 317 the boundary conditions are specified. The scenario is depicted in Figure 7.

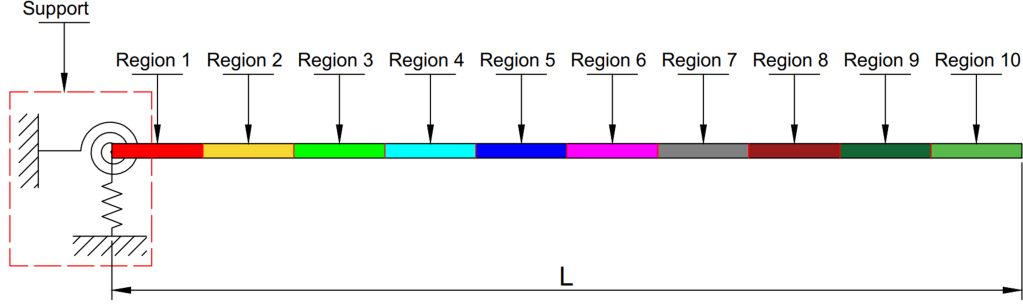


Figure 7: Beam geometry and boundary conditions.

318 The test consists in introducing a defect in region seven by reducing the
 319 Young modulus to 50%. Then, we solve equation (25) for obtaining the
 320 corresponding admissible fields used to calculate the indicator index from
 321 equation (35) for each region of the beam. Then, we solve equation (25) for
 322 obtaining the corresponding admissible fields used to calculate the indicator
 323 index from equation (35) for each region of the beam. The result is shown
 324 in Figure 8.

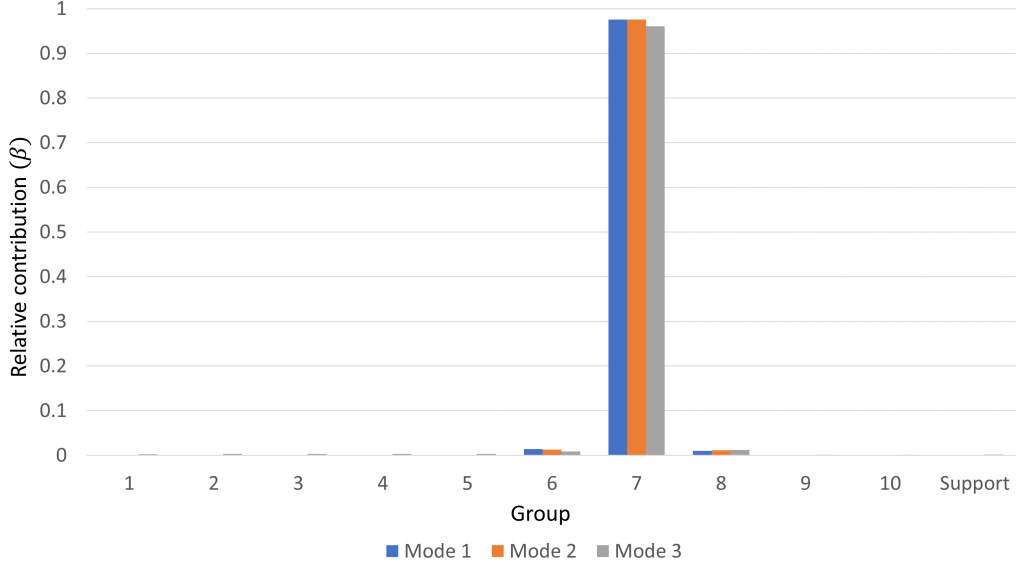


Figure 8: Contribution of each structural region to compose the global CRE, considering the first three mode shapes. Compared to the other regions, the prominence of the contribution shown by region seven indicates that it is poorly modelled.

325 Comparing the relative contribution of each region, it is possible to notice
 326 that region 7 has a β index around 0.97 for the first three modes of vibration.
 327 This information can be used to produce a more efficient identification algo-
 328 rithm because instead of identifying parameters of the structure as a whole,
 329 this procedure can be carried out by sub-zones, following the highest β values
 330 until global convergence is achieved.

331 Then, the test is repeated twice more. Firstly, the damage (50% of stiff-
 332 ness) is included in region 3. Then, the damage is additionally present in
 333 regions 1, 5 and 9. Figures 9 and 10 show the new distribution of β for
 334 each case. We observe that the prominence in the relative contribution cor-
 335 responds precisely where the defects are. However, note that the β levels
 336 do not remain the same for the different vibration modes. For instance, ac-
 337 cording to Figure 9, region 3 affects the first vibration mode much more than
 338 region 7. This information can be useful in designing real-life experiments, as
 339 it is possible to know in advance which mode of vibration must be mobilized
 340 to update the parameters of a particular region of the structure.

341 These tests show that the framework has a capacity to distinguish between
 342 well and poorly modelled zones in the constitutive relation error sense.

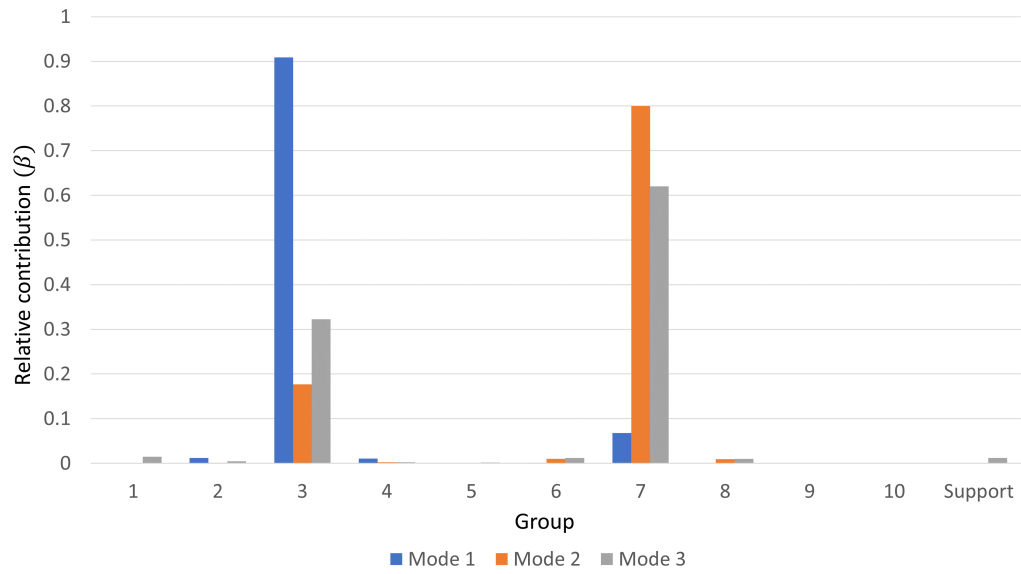


Figure 9: Contribution of each region of the structure to compose the global CRE, considering the first three modes. The prominence showed by regions 3, and 7 indicate they are being poorly modelled compared to the others.

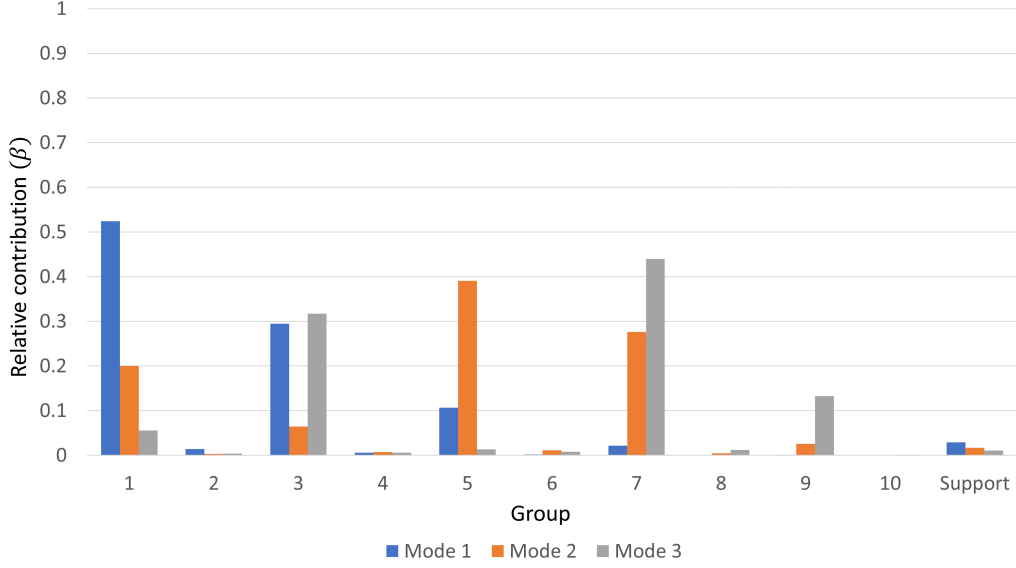


Figure 10: Contribution of each region of the structure to compose the global CRE, considering the first three modes. The prominence is shown by regions 1, 3, 5, 7 and 9; corresponding to the zones where damage is located.

343 5.2. Uni-parametric identification (beam-plate structure)

344 The typology of the present application is recurrent in the literature,
 345 being very useful in studying structural elements and their connections [18].
 346 Here, we are interested in identifying Young's modulus of the slabs in a three-
 347 storey building structure. Each slab is $4\text{ m} \times 4\text{ m}$ area and 0.15 m thickness.
 348 The cross-section is $40\text{ cm} \times 40\text{ cm}$ for pillars and $20\text{ cm} \times 50\text{ cm}$ for the beams.
 349 The material properties of pillars and beams are: Young modulus 32 GPa ,
 350 Poisson's ratio 0.2 and mass density 2500 kg/m^3 . The material properties
 351 are assumed the same for all slabs, making the problem a uni-parametric
 352 identification. The inter-floor distance is 3 m . In Figure 11, it is shown
 353 a three-dimensional view of the building and also the finite element model
 354 used.

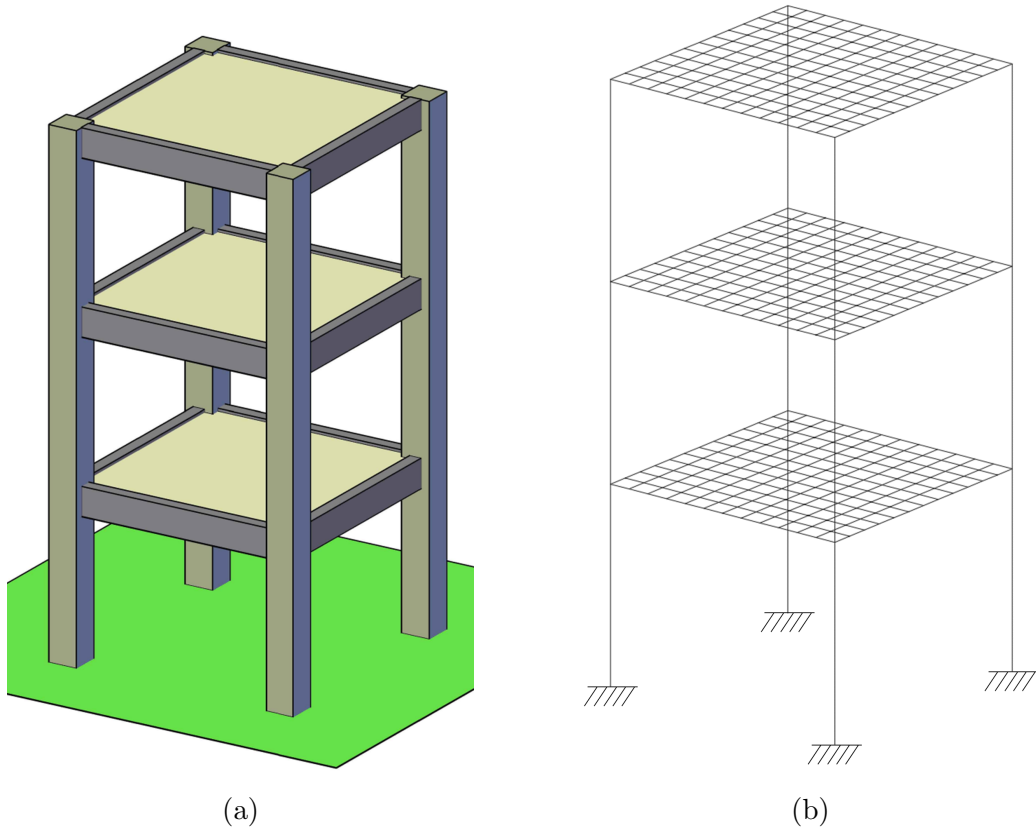


Figure 11: Building structure. (a) Three-dimensional representation. (b) Structural model composed of beams and plates.

355 The first three vibration modes used as reference are shown in Figure 12.
 356 They were obtained via forward analysis, assuming that slabs have the same
 357 material parameters as the columns and beams.

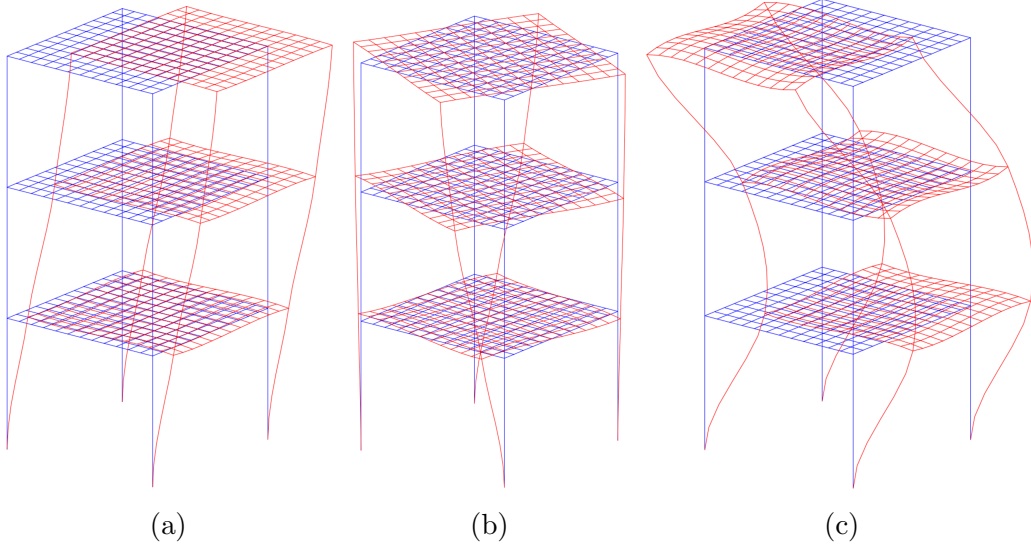


Figure 12: Building reference vibration modes: (a) Mode I, 4.34 Hz , (b) Mode II, 6.31 Hz , (c) Mode III, 14.24 Hz .

358 Setting the initial parameter value (θ_0) to 3.2 GPa , it is possible to follow
 359 the framework from Figure 2. The evolution of the MCRE as a function
 360 of θ/θ_{ref} can be seen in Figure 13. The logarithmic scale used to express
 361 the MCRE value shows the rapid convergence in the vicinity of the refer-
 362 ence value. When the algorithm finds the appropriate parameter value, the
 363 MCRE value tends to zero. This characteristic is preserved in cases such the
 364 present, where the reference modes are obtained numerically. In real-world
 365 problems, the zero value is rarely attainable due to the numerous sources of
 366 uncertainties associated with the measurements taken, the models employed
 367 and their respective solution techniques. Despite this, the trend of rapid lo-
 368 cal decrease in the MCRE values remains a good indicator for finding values
 369 of unknown parameters (θ).

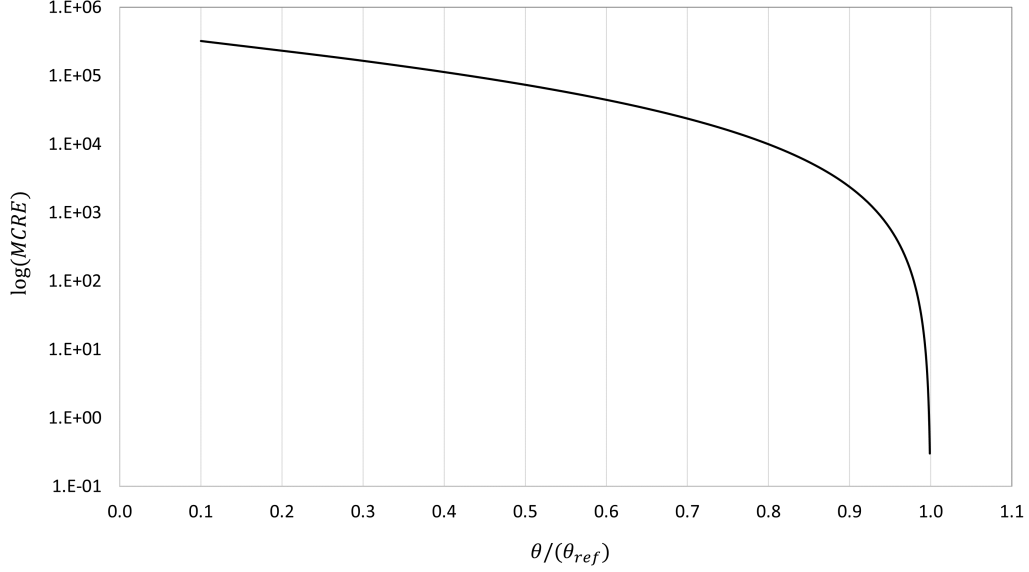


Figure 13: Identification of slabs stiffness. The searched parameter is identified when the MCRE value tends to zero.

370 This test permits observing that, in the absence of noise, the framework
 371 can find the correct value of the parameter sought even when the initial
 372 estimate is far from the reference. This property is desirable in numerical
 373 applications, as it helps to maintain good stability and convergence charac-
 374 teristics.

375 5.3. Multi-parametric identification (shell structure)

376 In this last application, one is interested in the behaviour of the framework
 377 when several parameters must be identified at the same time. For this end,
 378 it is proposed the identification of multiple stiffness parameters of a cooling
 379 tower. For sake of simplicity, only the shell structure is considered (adapted
 380 from [37]). Similarly to the first application, the tower is subdivided into five
 381 regions with their own material and geometric characteristics. The schematic
 382 scenario is illustrated in Figure 14. The regions high are $H_1 = 14.43\text{ m}$, $H_2 =$
 383 14.43 m , $H_3 = 157.50\text{ m}$, $H_4 = 43.80\text{ m}$ and $H_5 = 6.80\text{ m}$. The thickness of
 384 each region is $t_1 = 1.50\text{ m}$, $t_2 = 1.50\text{ m}$, $t_3 = 1.50\text{ m}$, $t_4 = 1.40\text{ m}$ and
 385 $t_5 = 1.0\text{ m}$. The diameters are $\phi_1 = 176.56\text{ m}$, $\phi_2 = 165.80\text{ m}$, $\phi_3 = 156.04\text{ m}$,
 386 $\phi_4 = 107.30\text{ m}$, $\phi_5 = 113.26\text{ m}$ and $\phi_6 = 114.18\text{ m}$. The base is prevented
 387 from moving in each of the three Cartesian directions.

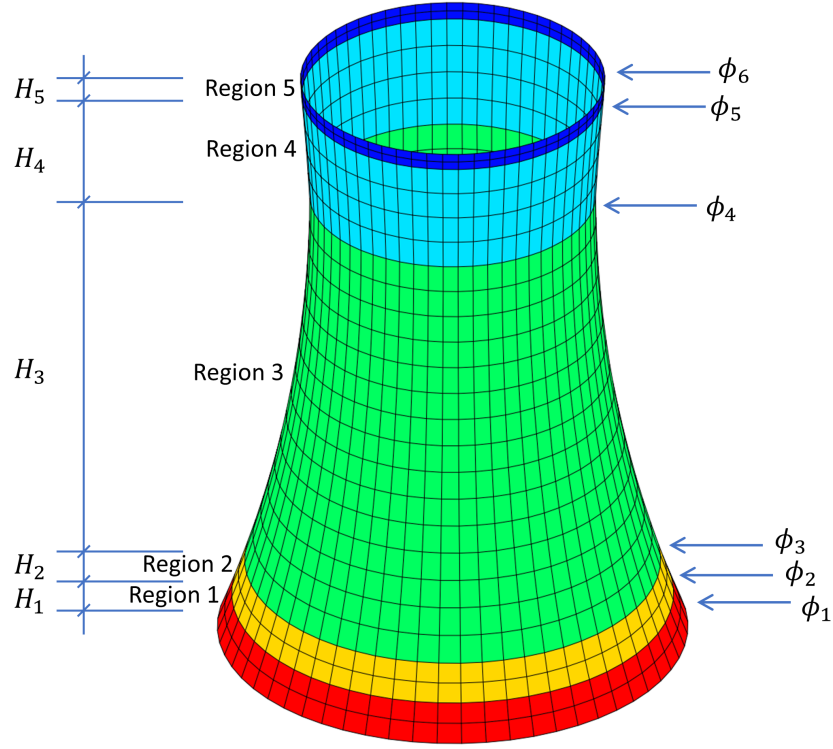


Figure 14: Cooling tower model (adapted from [37]).

388 The first three vibration modes used as a reference can be seen in Fig-
 389 ure 15. They were obtained through forward analysis using the following
 390 parameters, which are the same among all regions: Young modulus 32 GPa ,
 391 Poisson's ratio 0.2 and mass density 2500 kg/m^3 .

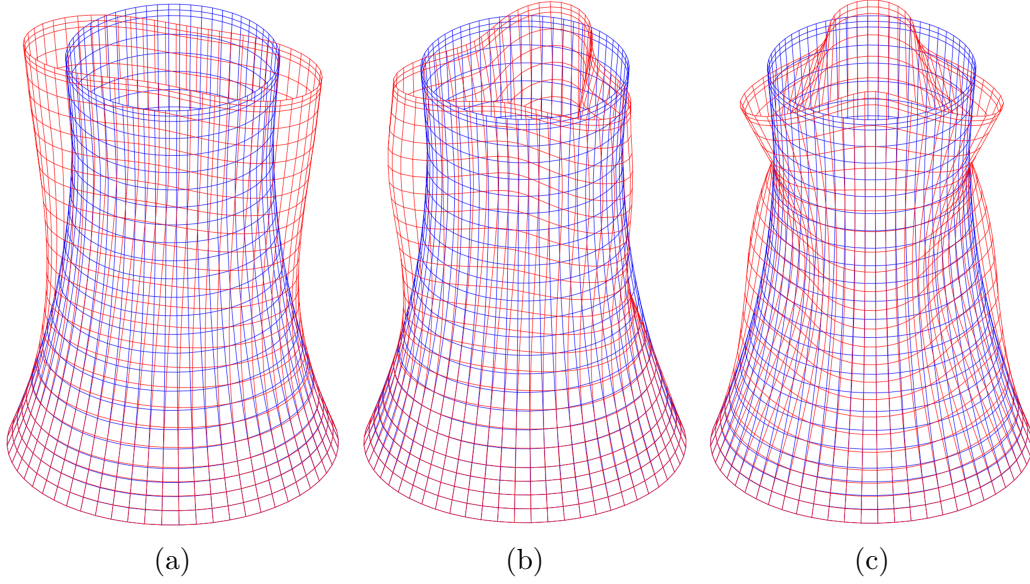


Figure 15: Cooling tower reference vibration modes: (a) Mode I, 0.90 Hz , (b) Mode II, 0.95 Hz , (c) Mode III, 1.20 Hz .

392 The parameters chosen to be identified are the Young moduli of regions
 393 2, 3, 4 and 5. The initial values setting are: $\theta_0 = \{16, 48, 16, 16\} \text{ GPa}$. The
 394 convergence history for the four chosen parameters can be seen in Figure 16.
 395 It is possible to notice that the convergence rate for each parameter is not
 396 the same. As the input data does not suffer any type of noise, all parameters
 397 could be identified correctly. In real-world scenarios, parameters with a low
 398 convergence rate can be drastically affected by uncertainties, and therefore
 399 filtering techniques may be helpful and can be coupled in the framework
 400 without major changes.

401 The value of the parameters is calculated based on the gradient method.
 402 However, the convergence curve shows that second-order algorithms such
 403 as BFGS can improve performance, which can also be implemented in the
 404 present framework.

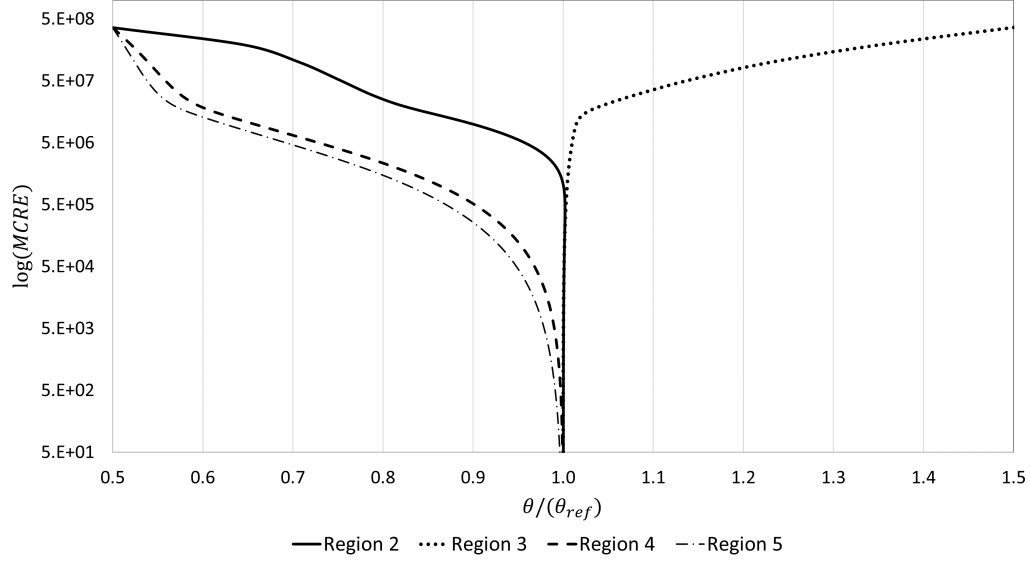


Figure 16: Cooling tower stiffness identification. The searched parameter corresponding to each region is identified when the MCRE value tends to zero.

405 What is pertinent to note from this test is that the framework, in the
 406 absence of measurement noise, is able to identify target parameters with
 407 high precision, even if they have low convergence rates or have vague initial
 408 estimates.

409 Concluding remarks

410 The present study dealt with the finite element model identification tech-
 411 nique based on Modified Constitutive Relation Error. This technique was
 412 used to design an open-source framework that identifies physical parameters,
 413 such as stiffness, in typical structural engineering situations. The framework
 414 was tested in representative scenarios of engineering practice in the absence
 415 of noise, and in all cases studied, it was able to identify the parameters sought
 416 accurately.

417 The results presented in this paper are far from exhaustive, and we do
 418 not have this intention either. We prefer to limit ourselves to proposing to
 419 the community of scientists and engineers an open-source code that can be
 420 used for educational and research purposes. Newcomers to the finite element
 421 model updating field can use the proposed framework to gain insights into the

422 domain. Also, they can use the provided codes as starting points for other
423 specific activities. Researchers may use the framework either to change it
424 according to their needs or as a black-box subroutine for complementary
425 codes.

426 The framework was developed in a modular way and is, therefore, able to
427 accommodate new functions and behaviours without significant changes. An
428 immediate extension would be the insertion of the effects of uncertainties or
429 physical nonlinearities. It is also possible to extend the present framework
430 to contemplate the cases of experiment design, in which the position and
431 quantity of sensors can be obtained even before starting the tests.

432 We believe that the present framework can be helpful to the model up-
433 dating community, both for a deeper study of the formulation properties and
434 for its expansion.

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