

Współrzędne cylindryczne (r, φ, z)

Gradient, dywergencja i laplasjan

$$\nabla\phi = \left(\frac{\partial\phi}{\partial r}, \frac{1}{r}\frac{\partial\phi}{\partial\varphi}, \frac{\partial\phi}{\partial z}\right) \quad \nabla\cdot\mathbf{u} = \frac{1}{r}\frac{\partial(ru_r)}{\partial r} + \frac{1}{r}\frac{\partial u_\varphi}{\partial\varphi} + \frac{\partial u_z}{\partial z} \quad \nabla^2\phi = \frac{1}{r}\frac{\partial}{\partial r}\left(r\frac{\partial\phi}{\partial r}\right) + \frac{1}{r^2}\frac{\partial^2\phi}{\partial\varphi^2} + \frac{\partial^2\phi}{\partial z^2}$$

Tensor naprężeń

$$\begin{aligned} \sigma_{rr} &= -p + 2\eta\frac{\partial u_r}{\partial r}, & \sigma_{\varphi\varphi} &= -p + 2\eta\left(\frac{1}{r}\frac{\partial u_\varphi}{\partial\varphi} + \frac{u_r}{r}\right), & \sigma_{zz} &= -p + 2\eta\frac{\partial u_z}{\partial z}, \\ \sigma_{\varphi z} &= \eta\left(\frac{1}{r}\frac{\partial u_z}{\partial\varphi} + \frac{\partial u_\varphi}{\partial z}\right), & \sigma_{rz} &= \eta\left(\frac{\partial u_r}{\partial z} + \frac{\partial u_z}{\partial r}\right), \\ \sigma_{r\varphi} &= \eta\left(\frac{\partial u_\varphi}{\partial r} - \frac{u_\varphi}{r} + \frac{1}{r}\frac{\partial u_r}{\partial\varphi}\right). \end{aligned}$$

Równanie Naviera-Stokesa

$$\begin{aligned} \frac{\partial u_r}{\partial t} + (\vec{u}\nabla)u_r - \frac{u_\varphi^2}{r} &= -\frac{1}{\rho}\frac{\partial p}{\partial r} + \nu\left(\Delta u_r - \frac{u_r}{r^2} - \frac{2}{r^2}\frac{\partial u_\varphi}{\partial\varphi}\right), \\ \frac{\partial u_\varphi}{\partial t} + (\vec{u}\nabla)u_\varphi + \frac{u_\varphi u_r}{r} &= -\frac{1}{\rho r}\frac{\partial p}{\partial\varphi} + \nu\left(\Delta u_\varphi - \frac{u_\varphi}{r^2} + \frac{2}{r^2}\frac{\partial u_r}{\partial\varphi}\right), \\ \frac{\partial u_z}{\partial t} + (\vec{u}\nabla)u_z &= -\frac{1}{\rho}\frac{\partial p}{\partial z} + \nu\Delta u_z. \end{aligned}$$

Równanie ciągłości

$$\frac{1}{r}\frac{\partial(ru_r)}{\partial r} + \frac{1}{r}\frac{\partial u_\varphi}{\partial\varphi} + \frac{\partial u_z}{\partial z} = 0.$$

Współrzędne sferyczne (r, θ, φ)

Gradient, dywergencja i laplasjan

$$\begin{aligned} \nabla\phi &= \left(\frac{\partial\phi}{\partial r}, \frac{1}{r}\frac{\partial\phi}{\partial\theta}, \frac{1}{r\sin\theta}\frac{\partial\phi}{\partial\varphi}\right) \quad \nabla\cdot\mathbf{u} = \frac{1}{r^2}\frac{\partial(r^2u_r)}{\partial r} + \frac{1}{r\sin\theta}\frac{\partial(\sin\theta u_\theta)}{\partial\theta} + \frac{1}{r\sin\theta}\frac{\partial u_\varphi}{\partial\varphi} \\ \nabla^2\phi &= \frac{1}{r^2}\frac{\partial}{\partial r}\left(r^2\frac{\partial\phi}{\partial r}\right) + \frac{1}{r^2\sin\theta}\frac{\partial}{\partial\theta}\left(\sin\theta\frac{\partial\phi}{\partial\theta}\right) + \frac{1}{r^2\sin^2\theta}\frac{\partial^2\phi}{\partial\varphi^2} \end{aligned}$$

Tensor naprężen

$$\begin{aligned}\sigma_{rr} &= -p + 2\eta \frac{\partial u_r}{\partial r}, & \sigma_{\theta\theta} &= -p + 2\eta \left(\frac{1}{r} \frac{\partial u_\theta}{\partial \theta} + \frac{u_r}{r} \right), & \sigma_{\varphi\varphi} &= -p + 2\eta \left(\frac{1}{r \sin \theta} \frac{\partial u_\varphi}{\partial \varphi} + \frac{u_\theta}{r} \operatorname{ctg} \theta + \frac{u_r}{r} \right), \\ \sigma_{\theta\varphi} &= \eta \left(\frac{1}{r} \frac{\partial u_\varphi}{\partial \theta} - \frac{1}{r} u_\varphi \operatorname{ctg} \theta + \frac{1}{r \sin \theta} \frac{\partial u_\theta}{\partial \varphi} \right), \\ \sigma_{r\theta} &= \eta \left(\frac{\partial u_\theta}{\partial r} - \frac{u_\theta}{r} + \frac{1}{r} \frac{\partial u_r}{\partial \theta} \right), & \sigma_{\varphi r} &= \eta \left(\frac{1}{r \sin \theta} \frac{\partial u_r}{\partial \varphi} + \frac{\partial u_\varphi}{\partial r} - \frac{u_\varphi}{r} \right).\end{aligned}$$

Równanie Naviera-Stokesa

$$\begin{aligned}\frac{\partial u_r}{\partial t} + (\vec{u} \nabla) u_r - \frac{u_\theta^2 + u_\varphi^2}{r} &= -\frac{1}{\rho} \frac{\partial p}{\partial r} + \nu \left[\Delta u_r - \frac{2u_r}{r^2} - \frac{2}{r^2 \sin \theta} \frac{\partial (u_\theta \sin \theta)}{\partial \theta} - \frac{2}{r^2 \sin \theta} \frac{\partial u_\varphi}{\partial \varphi} \right], \\ \frac{\partial u_\theta}{\partial t} + (\vec{u} \nabla) u_\theta + \frac{u_r u_\theta}{r} - \frac{u_\varphi^2 \operatorname{ctg} \theta}{r} &= -\frac{1}{\rho r} \frac{\partial p}{\partial \theta} + \nu \left[\Delta u_\theta + \frac{2}{r^2} \frac{\partial u_r}{\partial \theta} - \frac{u_\theta}{r^2 \sin^2 \theta} - \frac{2 \cos \theta}{r^2 \sin^2 \theta} \frac{\partial u_\varphi}{\partial \varphi} \right], \\ \frac{\partial u_\varphi}{\partial t} + (\vec{u} \nabla) u_\varphi + \frac{u_r u_\varphi}{r} - \frac{u_\varphi u_\theta \operatorname{ctg} \theta}{r} &= -\frac{1}{\rho} \frac{\partial p}{\partial \varphi} + \nu \left[\Delta u_\varphi + \frac{2}{r^2 \sin \theta} \frac{\partial u_r}{\partial \varphi} + \frac{2 \cos \theta}{r^2 \sin^2 \theta} \frac{\partial u_\theta}{\partial \varphi} - \frac{u_\varphi}{r^2 \sin^2 \theta} \right].\end{aligned}$$

Równanie ciągłości

$$\frac{1}{r^2} \frac{\partial (r^2 u_r)}{\partial r} + \frac{1}{r \sin \theta} \frac{\partial (\sin \theta u_\theta)}{\partial \theta} + \frac{1}{r \sin \theta} \frac{\partial u_\varphi}{\partial \varphi} = 0.$$

Dla przestrzeni euklidesowej zachodzą następujące tożsamości wektorowe:

1. $\operatorname{rot} \operatorname{rot} \vec{v} = \operatorname{grad} \operatorname{div} v - \Delta \vec{v}$
2. $\operatorname{grad}(\vec{u} \cdot \vec{v}) = (\vec{u} \cdot \operatorname{grad}) \vec{v} + (\vec{v} \cdot \operatorname{grad}) \vec{u} + \vec{u} \times \operatorname{rot} \vec{v} + \vec{v} \times \operatorname{rot} \vec{u}$
3. $\operatorname{rot}(\vec{u} \times \vec{v}) = \vec{u} \operatorname{div} \vec{v} + (\vec{v} \cdot \operatorname{grad}) \vec{u} - \vec{v} \operatorname{div} \vec{u} - (\vec{u} \cdot \operatorname{grad}) \vec{v}$
4. $\operatorname{div}(\vec{u} \times \vec{v}) = \vec{u} \cdot \operatorname{rot} \vec{v} - \vec{v} \cdot \operatorname{rot} \vec{u}$
5. $\operatorname{div} \operatorname{rot} \vec{u} = 0$
6. $\operatorname{rot} \operatorname{grad} \varphi = 0$